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AN INVESTIGATION INTO SAFETY OF PASSAGE OF LARGE TANKERS IN THE--ETC(U)

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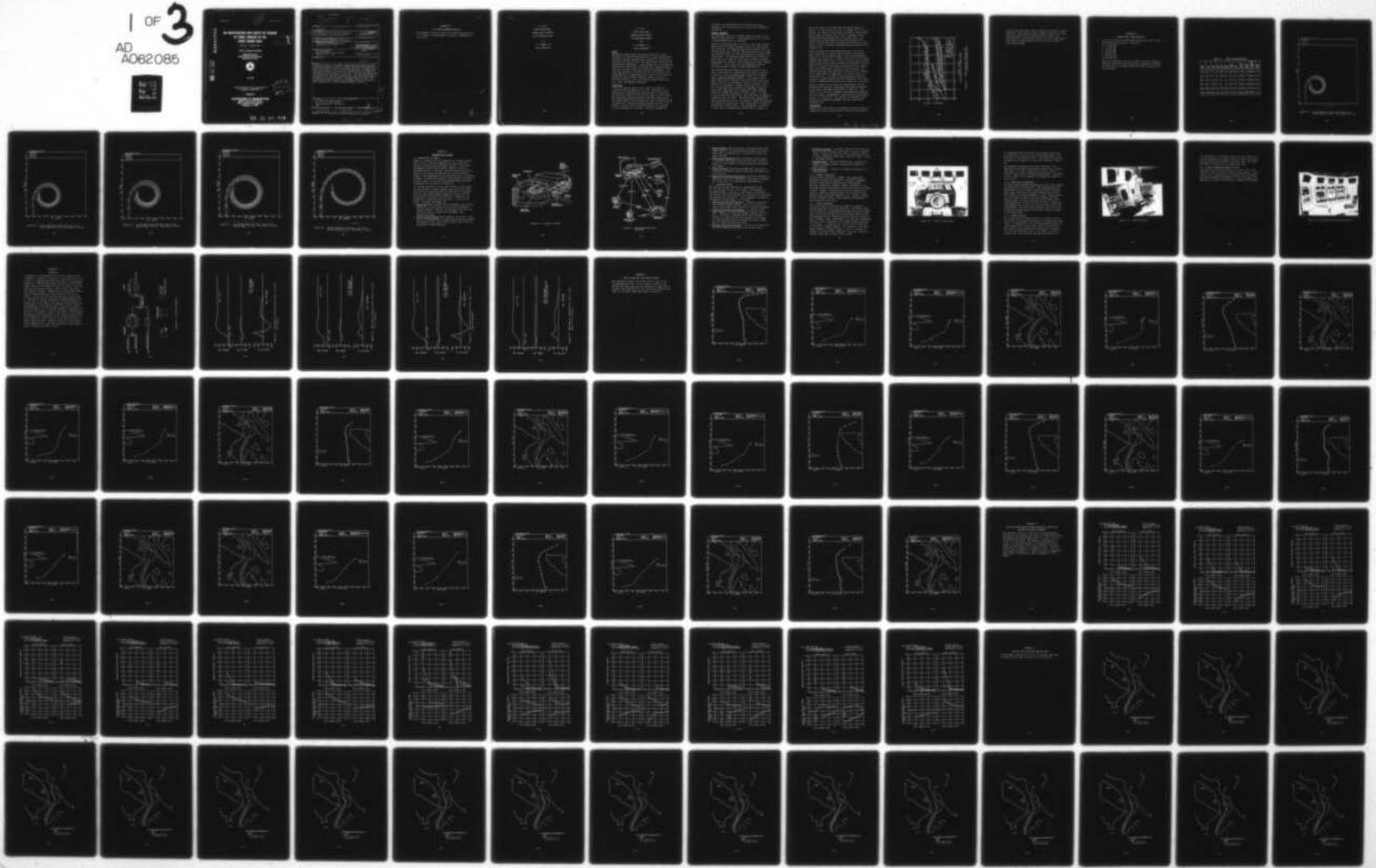
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1 OF 3
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Report No.

Vol. 2 of 2

ADA062085

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AN INVESTIGATION INTO SAFETY OF PASSAGE OF LARGE TANKERS IN THE PUGET SOUND AREA

LEVEL III

VOLUME II:APPENDICES

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July 1978

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| 16. Abstract A study was conducted at the Computer Aided Operations Research Facility to investigate the safety of passage of tankers through the Puget Sound area under maximum credible adverse environmental conditions. The study was conducted in two phases: off-line, using a computer program to simulate the performance of various size tankers, and on-line utilizing the CAORF simulator with human test subjects. In each phase, there were two types of runs: track keeping runs, and failed equipment runs. The track keeping results indicated that all ships were able to navigate safely under the extreme environmental conditions provided they maintained sufficient speed. The failed equipment runs indicated that tug support of ships was required to avoid grounding after suffering steering/propulsion failures. | | |
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APPENDIX A
TUG FORCE REFERENCE MATERIAL

This appendix contains a copy of the data submitted by Mr. C. R. Horton, an acknowledged tug expert recommended by the U.S.C.G.



C.A.O.R.F.
PUGET SOUND AREA
TANKER SAFETY PROJECT
TUG ASSISTANCE STUDY

by
C. R. HORTON, JR.
NAVAL ARCHITECT

C.A.O.R.F.

PUGET SOUND AREA

TANKER SAFETY PROJECT

TUG ASSISTANCE STUDY

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NAVAL ARCHITECT

SCOPE

The subject study covers the potential ability of tug assistance to provide safe operation of large tankers while entering, leaving, and docking at terminals in the area of the Straits of Juan de Fuca, and Puget Sound, Anacortes and Cherry Point, Washington. It was agreed that the preferable system would involve use of the tugs that already operate in the area, but that other types should be considered. This study was required to furnish data for both, based on the requirements for stopping and controlling a ship having tug assistance when the ship suffered a power failure or a steering failure or both, and under the most adverse current, wind, and weather conditions.

CONDITIONS

A list of existing tugs by type, power, and method of propulsion was furnished by C.A.O.R.F. Discussion of the problem led to narrowing the required data to the forces that could be applied to the ship by tugs of various types and power when already attached to the ship under escort. The forces should cover the expected range of speeds through the water for a ship maintaining steering control in the channel, current, wind, and water depths to be expected, not the free speed of the ship. Six knots through the

the water, or three knots over the bottom in either adverse or fair currents up to six knots were considered reasonable.

GENERAL COMMENTS

The available tugs are of several types and cover a wide range of power and pull. Some explanatory notes will help in understanding the data supplied.

None of the existing tugs is a tractor type, which modern practice would consider the best choice for these duties. Data given for the flanking rudder astern nozzle type, the Z drive nozzle type, and the Voith-Schneider tractor types are therefore only for future construction or charter from other areas. The flanking rudder-astern nozzle type has been built up to 6000 H.P. and is not limited in maximum power except by available lines and bitts on ships, perhaps 10,000 H.P. The Z drive and Voith-Schneider tugs are believed limited in power to about 4000-5000 H.P.

The existing tugs can operate as attached escort tractor tugs at the stern of a large ship, with hawser attached at the bow, over the desired speed range up to 10 knots ahead, assuming adequate hawsers. In stopping a ship, these tugs can pull directly astern only until near zero speed, and if it is necessary to exert a lateral force on the ship to counteract a rudder failed hard over or the bias of backing ship's propeller in emergency stopping conditions, they would not be adequate. When creating stern way through the water in a fair current, in order to stop a ship over the bottom, they would have to change to towing over the tug stern. This would take considerable time to accomplish, say 8 to 10 minutes, unless the existing bow hawser was already led to the riding ring or sling was arranged for quick release. This arrangement is similar to that used on seagoing push towing tugs in a notch, so

that they can go on a hawser when the weather gets too severe. It would reduce the time for change over to 2 to 3 minutes, but requires very careful handling at high forward ship's speed, and would only be done at perhaps 3 knots through the water maximum due to the danger and to the limitation of astern speed on the existing tugs due to lack of control when they were being towed astern of their hawser, as well as weather considerations and generally low freeboard aft.

After reversing the tug as described above, and as the ship's speed went to astern and increased, the existing tugs, and in fact any known type of tug, would gradually largely lose its ability to exert lateral force on the ship combined with astern force, so that at about 8 knots astern only a nearly direct astern pull would be possible, and the degree of control of the ship would depend on the current, wind, and failed rudder or ship's forces existing. The reversed existing tugs, especially those with Kort nozzles, would, under these circumstances, do as well as any, but at greater risk. All types of tug propulsion gradually lose pull as speed through the water increases, or as the control elements produce forces at an angle with the hawser.

Several studies of tug forces and requirements for safe handling and docking of large ships have been conducted in recent years, and some current work is under way. The studies of the British, Japanese, and Canadian governments are very useful, and Marad/U.S. Coast Guard are performing tests on a Z drive tug. The results are reasonably consistent and in general agreement with the conclusions expressed here.

CONCLUSIONS

Figure A-1 of this report is intended to show the astern or stopping pull which the existing tug types and alternative

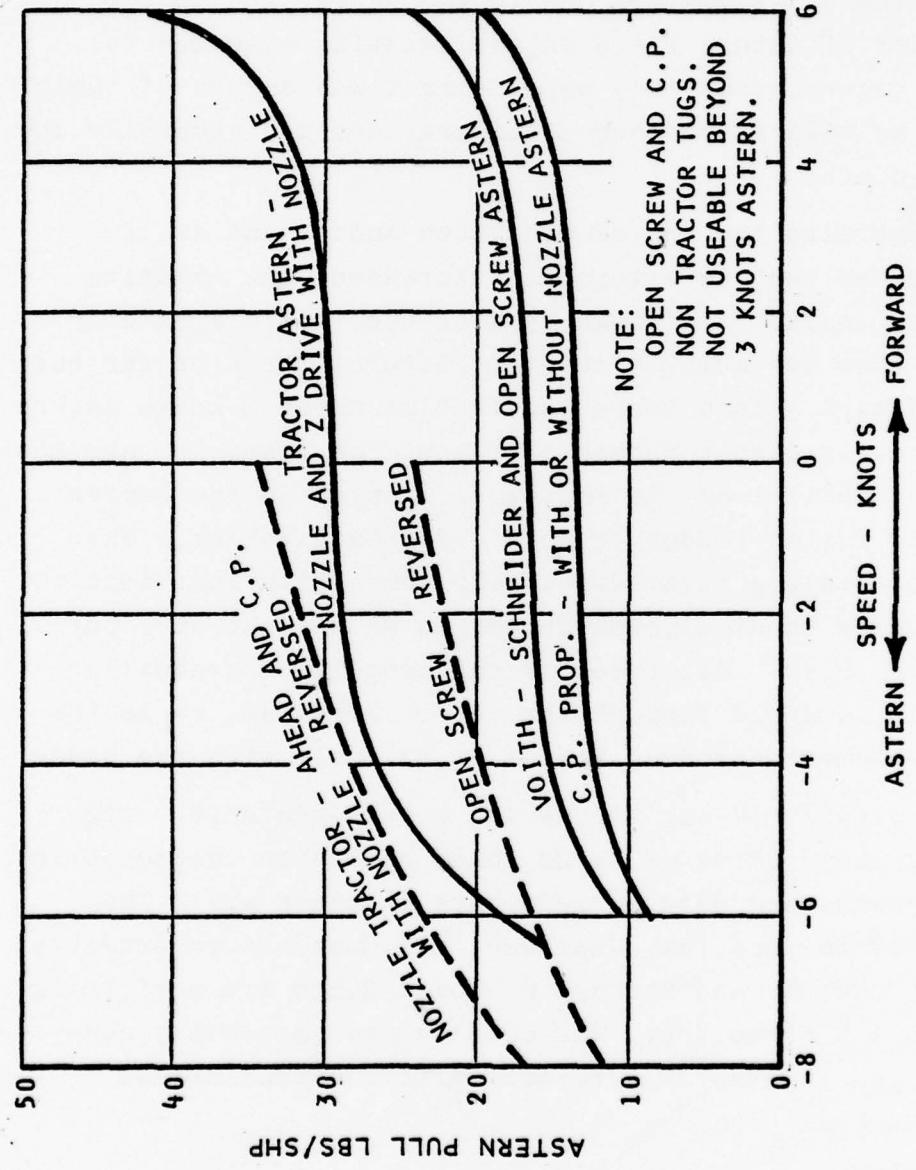


Figure A-1. CAORF Study Tug Stopping Pull
(use 80% for Actual Pull).

tractor tugs could exert when in position following a tanker under way. The tugs would have a hawser attached at the bow and would exert the pulls shown directly astern. The existing tugs of either open screw, C.P. with rudder nozzle, twin screw or single screw, would be limited to about 3 knots astern speed.

APPENDIX B

TANKER MODEL CHARACTERISTICS

A total of six fully loaded tanker models were used in the Puget Sound investigation. They were:

- 40,000 DWT
- 80,000 DWT
- 120,000 DWT
- 165,000 DWT
- 280,000 DWT
- 400,000 DWT

Table B-1 contains a listing of some of the more important physical characteristics of each ship; Figures B-1 through B-5 show the plot of high speed, hard right turning circle for each ship.

TABLE B-1. VESSEL CHARACTERISTICS

| Vessel Type | Lpp (ft) | Beam (ft) | Depth (ft) | Draft (ft) | Block Coeff | Prop. Diam (ft) | Pitch (ft) | Displace-ment (tons) | Rudder Area (ft ²) | Wetted Hull Profile Area (ft ²) | Rudder Area Ratio |
|-------------|----------|-----------|------------|------------|-------------|-----------------|------------|----------------------|--------------------------------|---|-------------------|
| 40K | 597 | 90 | 49.5 | 36.9 | 0.77 | 19.03 | 13.06 | 43,618 | 396.5 | 22029.3 | 0.018 |
| 80K | 763 | 125 | 59 | 39.9 | 0.8 | 23.0 | 18.4 | 86,982 | 517.5 | 30443.7 | 0.017 |
| 120K | 850 | 145 | 67 | 47 | 0.8 | 26.5 | 21.3 | 142,852 | 747.8 | 43987.5 | 0.017 |
| 165K | 951 | 155.4 | 71 | 52 | 0.81 | 26.0 | 19.6 | 180,550 | 746.3 | 49756.3 | 0.015 |
| 280K | 1066.3 | 173.9 | 92.9 | 72.35 | 0.83 | 29.86 | 21.3 | 318,928 | 1388.7 | 77149.0 | 0.018 |
| 400K | 1148.35 | 230.0 | 92.2 | 72.91 | 0.83 | 31.8 | 21.3 | 465,000 | 1590.8 | 83726.2 | 0.019 |

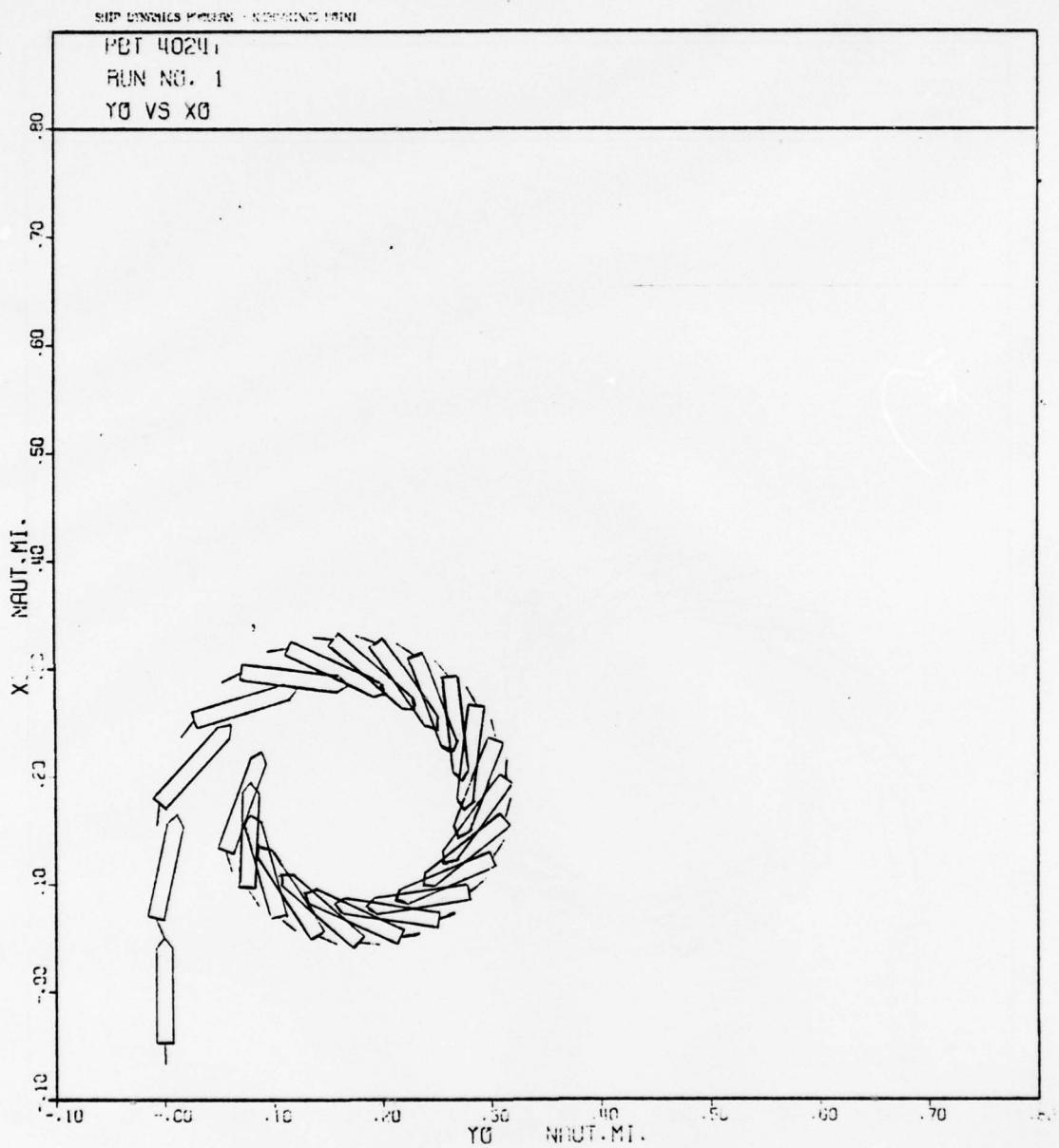


Figure B-1. 40,000 DWT Tanker 35° Right Turn Circle.
Initial Speed = 14 kts. Plot Freq. = 30 sec.

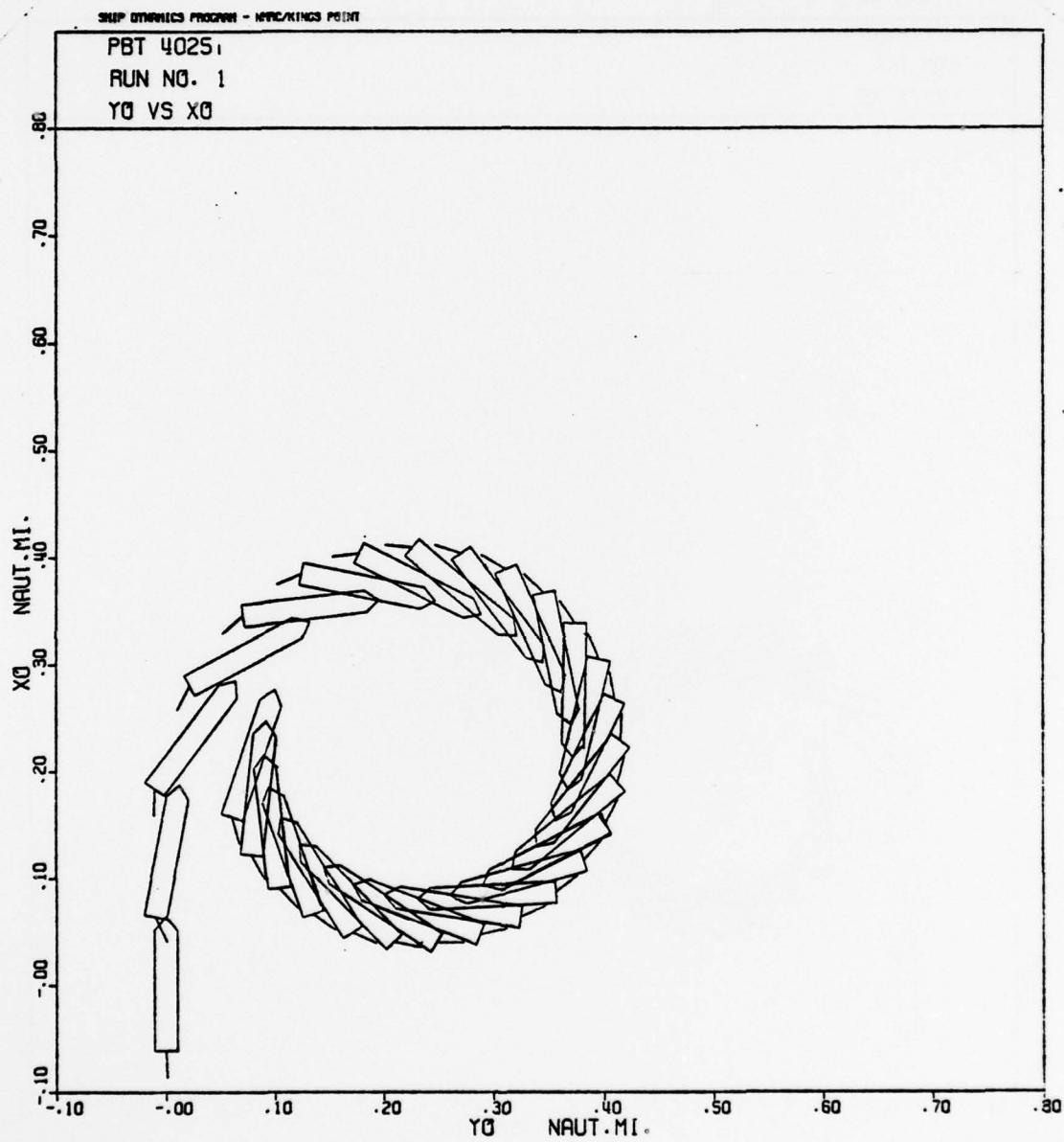


Figure B-2. 80,000 DWT Tanker 35° Right Turn Circle.
Initial Speed = 15 kts. Plot Freq. = 30 sec.

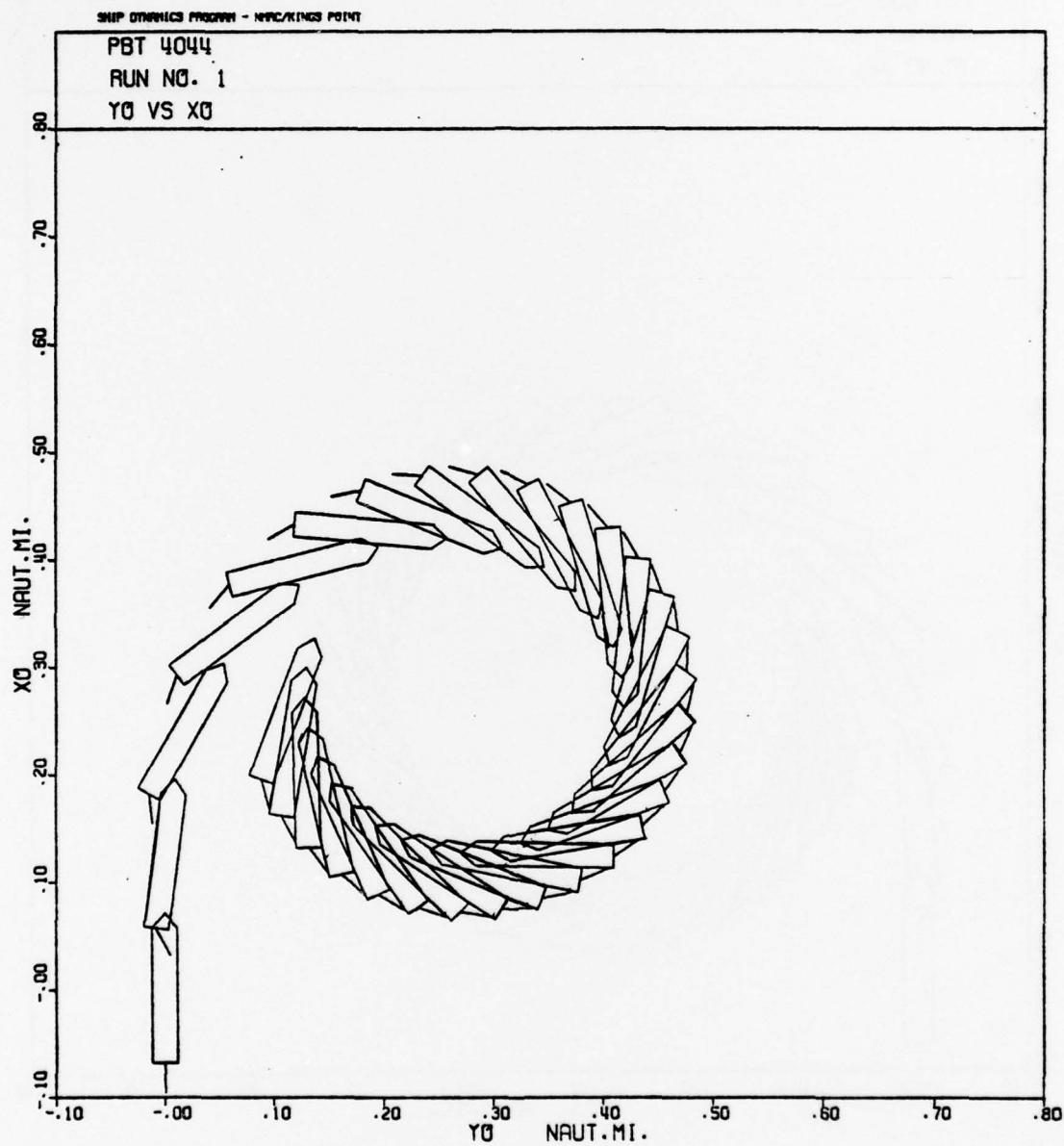


Figure B-3. 120,000 DWT Tanker 35° Right Turn Circle.
Initial Speed = 15 kts. Plot Freq. = 30 sec.

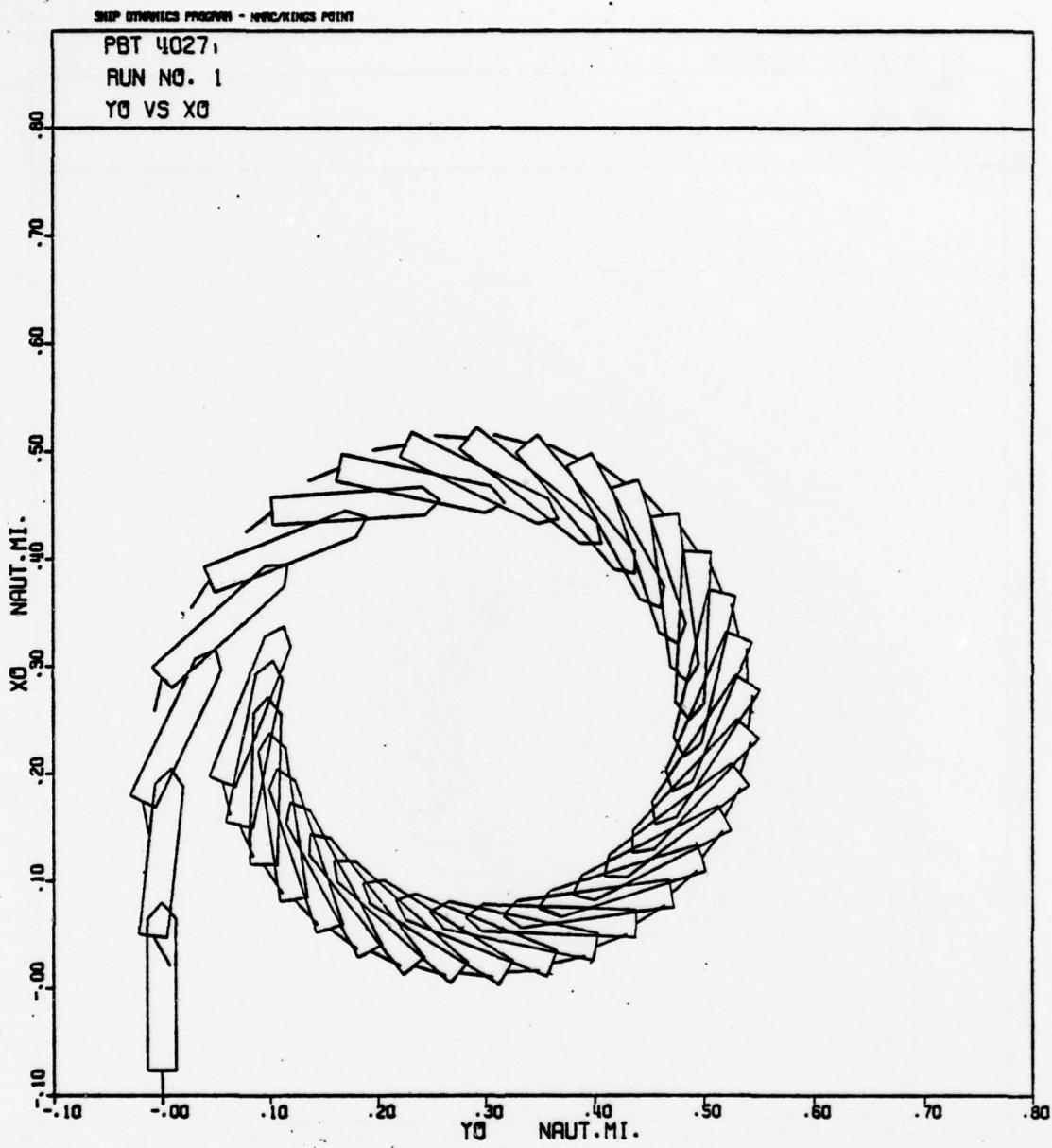


Figure B-4. 165,000 DWT Tanker 35° Right Turn Circle.
Initial Speed = 15 kts. Plot Freq. = 30 sec.

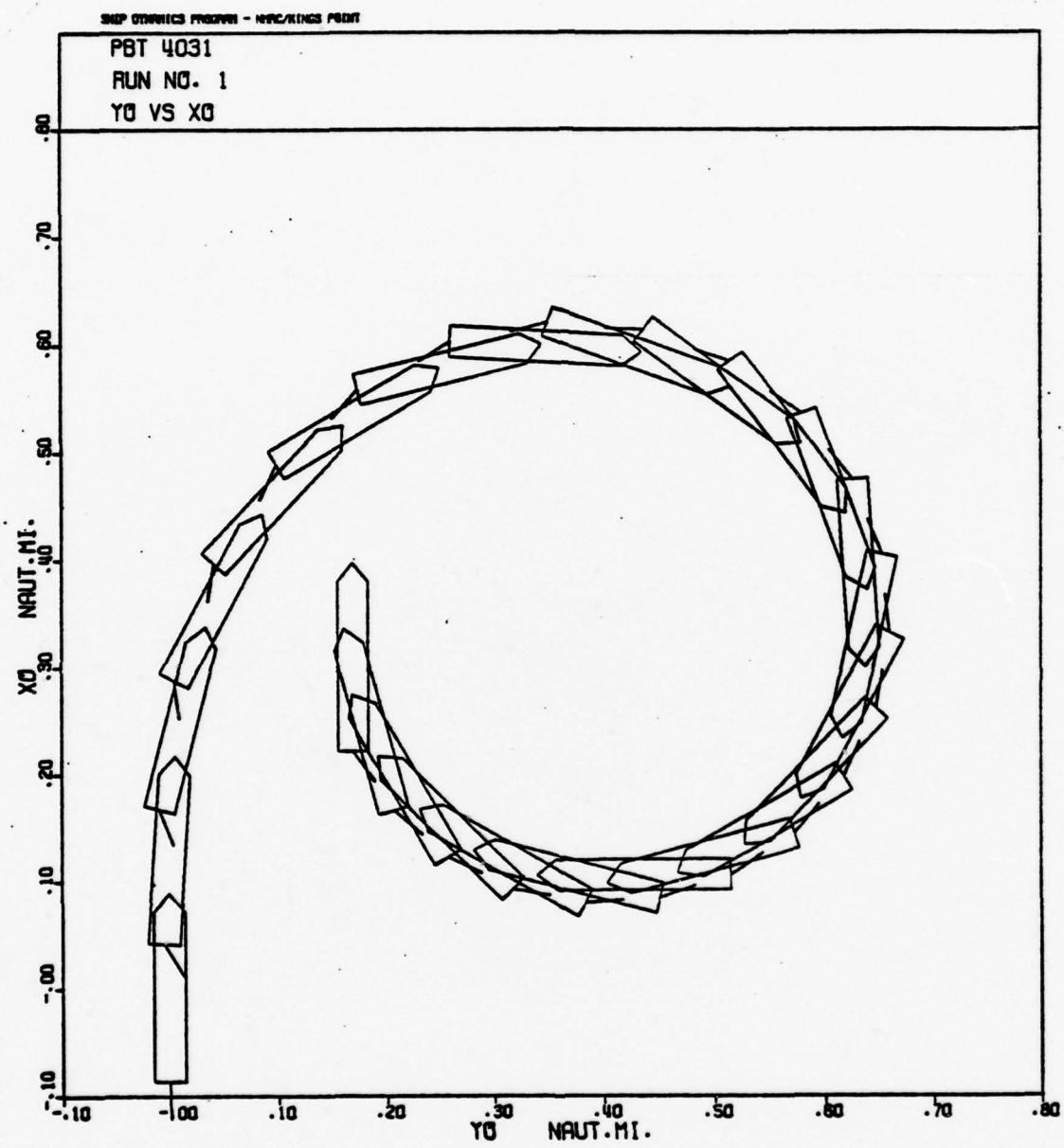


Figure B-5. 280,000 DWT Tanker 35° Right Turn Circle.
Initial Speed = 15 kts. Plot Freq. = 30 sec.

APPENDIX C

DESCRIPTION OF CAORF

C-1 DESCRIPTION OF CAORF

CAORF is a sophisticated ship-maneuvering simulator operated by the U.S. Maritime Administration for controlled research into man-ship-environment problems. Controlled experiments, which require several vessels, cannot be performed readily in the real world and would certainly be ruled out for testing situations that involve potential danger. Such experiments can be performed safely and easily at CAORF. A simplified cutaway of the simulator building is shown in Figure C-1 and the relationships among the major subsystems are illustrated in Figure C-2.

All actions called for by the watch officer on the bridge are fed through a central computer that alters the visual scene and all bridge displays and repeaters in accordance with the calculated dynamic response of ownship and the environmental situation being simulated. CAORF has the capability of simulating any ship, port, or area in the world. The major subsystems are:

- Wheelhouse which contains all the equipment and controls needed by the test subject watch officer to maneuver ownship through a scenario, and includes propulsion and steering controls, navigational equipment, and communication gear
- Central Data Processor which computes the motion of ownship in accordance with its known characteristics, models the behavior of all other traffic ships, and drives the appropriate bridge indicators

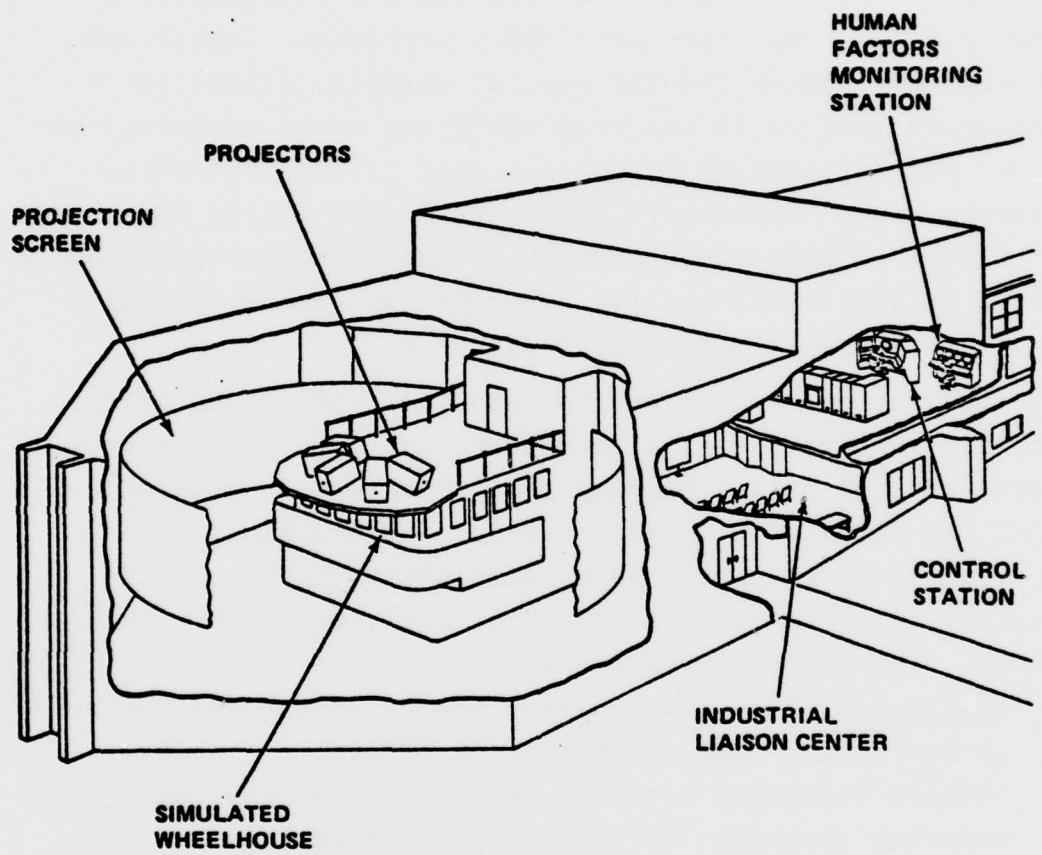


Figure C-1. Cutaway of CAORF.

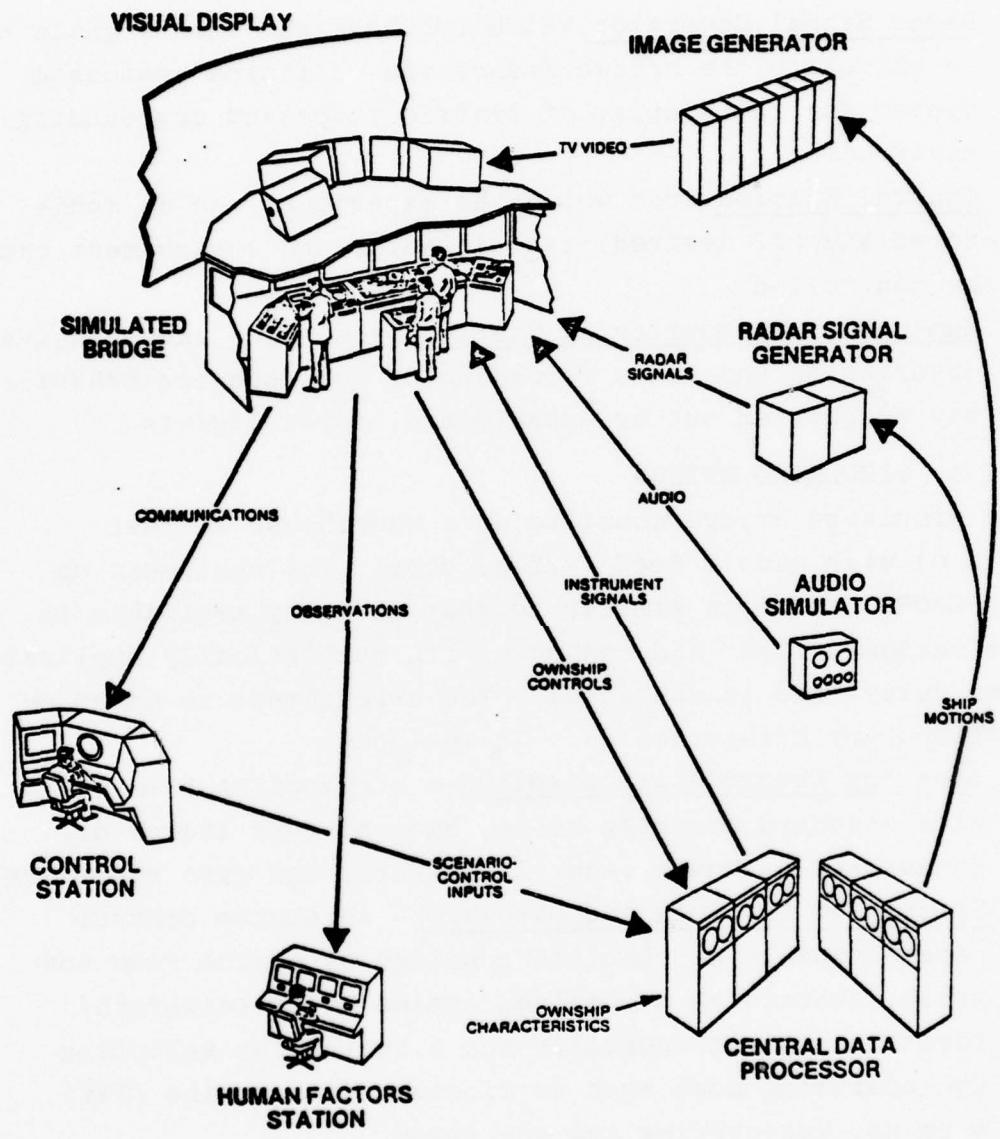


Figure C-2. Relationships Among Major Subsystems.

- Image Generator which constructs the computer-generated visual image of the surrounding environment and traffic ships that is projected onto a cylindrical screen for visual realism
- Radar Signal Generator which synthesizes video signals to stimulate the bridge radars and collision avoidance system for the display of traffic ships and surrounding environment
- Control Station from which the experiment can be monitored and (if desired) traffic ships and environment can be controlled
- Human Factors Monitoring Station from which unobtrusive observation and video recording of test subject behavior may be carried out by experimental psychologists

C.1.1 SIMULATED BRIDGE

The simulated bridge consists of a wheelhouse 20 feet (6.1 m) wide and 14 feet (4.3 m) deep. The equipment on the CAORF bridge is similar to that normally available in the merchant fleet and responds with realistically duplicated time delays and inaccuracies. The arrangement is based on contemporary bridge design. It includes:

- Steering Controls and Displays - a gryopilot helm unit with standard steering modes, rate of turn indicator, rudder angle/rudder order indicators, and gyro repeaters
- Propulsion Controls and Displays - an engine control panel (capable of simulating bridge or engine room control), containing a combined engine order telegraph/throttle, an rpm indicator and a switch for selecting the operating mode such as finished with engine (FWE), warm up, maneuvering and sea speed
- Thruster Controls and Display - bow and stern thrusters and their respective indicators and status lights

- Navigation Systems - two radars capable of both relative and true motion presentations plus a collision avoidance system. Capability exists for future additions such as a digital fathometer, RDF (Radio Direction Finder), Loran C, and Omega systems
- Communications - simulated VHF/SSB radio, docking loud-speaker (talkback) system, sound powered phones and ship's whistle
- Wind Indicators - indicate true speed and direction of simulated wind.

C.1.2 OWNSHIP SIMULATION

Any ship may be simulated at CAORF. The computerized equations of motion are adapted to the ship by changing specific coefficients among which are hydrodynamics, inertial, propulsion, thruster, rudder, aerodynamic, etc. Wind and currents realistically affect ship motion according to draft (loaded or ballasted) and relative speed and direction. Ownship's computer model was validated by comparing various simulated maneuvers (e.g., zig-zag, turning circle, and spiral tests, crash stops and acceleration) with actual sea trial data.

C.1.3 IMAGE GENERATION

The visual scene is duplicated on CAORF to a degree of realism sufficient for valid simulation. The scene (Figure C-3) includes all the man-made structures and natural components of the surrounding scene that mariners familiar with the geographical area deem necessary as cues for navigation. Thus, bridges, buoys, lighthouses, tall buildings, mountains, glaciers, piers, coastlines, and islands would be depicted in the scene. In addition, the closest traffic ships and the forebody of ownship appear. All elements in the scene, except ownship's forebody, appear to move in response to ownship's and other ship's maneuvers. The sky is depicted without clouds and the water without waves.

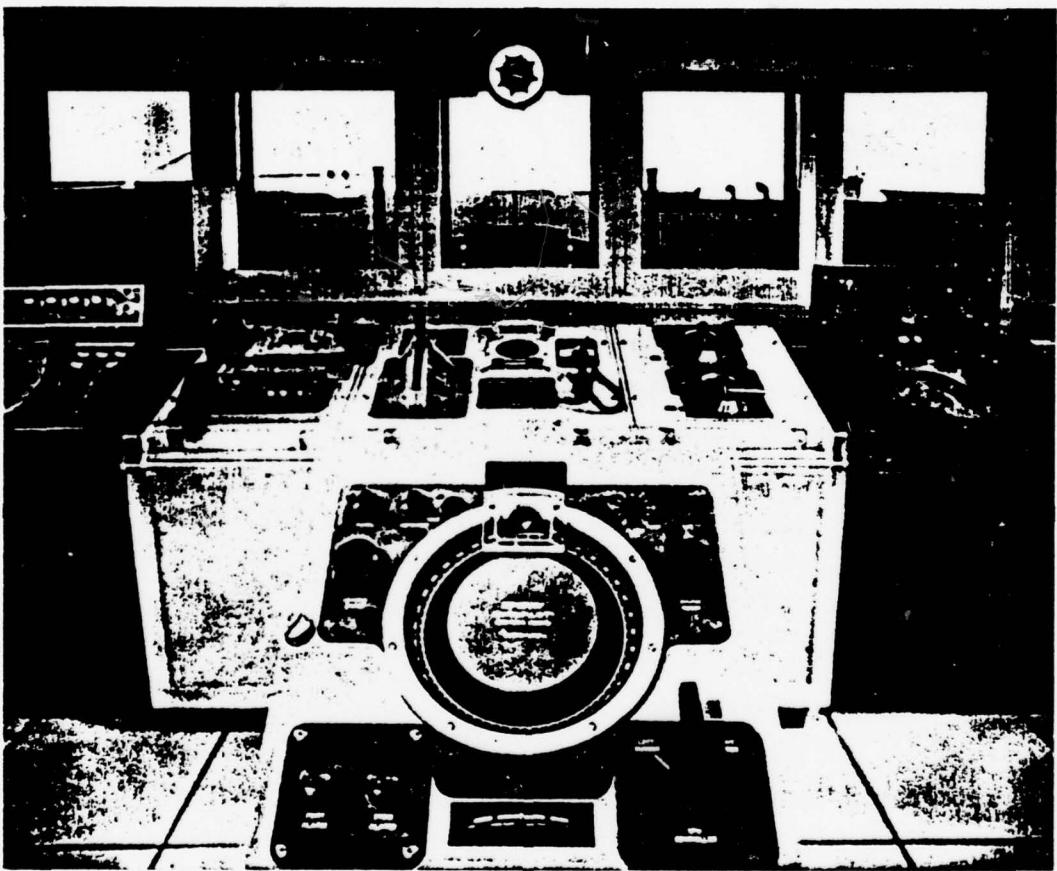


Figure C-3. Typical Visual Scene

For enhanced realism the scene is projected in full color. The perspective is set for the actual bridge height above waterline for the simulated ship. Shadowing can be varied according to the position of the sun at different times of day.

Environmental conditions also affect the scene. The lighting can be varied continuously from full sun to moonless night. At night, lights can be seen on traffic vessels, buoys, piers, and other points ashore. Visibility in day or night can be reduced to simulate any degree of fog or haze.

C.1.4 RADAR SIGNAL GENERATION

The Radar Signal Generator produces real-time video signals for driving the two radar PPIS. The items displayed are synchronized with the visual scene and include navigation aids, ships, shoreline and other topographical features with appropriate target shadowing, clutter, range attenuation, and receiver noise. The radar gaming area which covers an area of 150 by 200 miles, extends beyond the visual gaming area, which is 50 by 100 miles. Within the radar gaming area, as many as 40 moving traffic ships can be displayed. The radar signal generator also drives the collision avoidance system, which can be slaved to either of the master PPIS.

C.1.5 CONTROL STATION

The control station (Figure C-4) is the central location from which the simulator experiment is controlled and monitored. An experiment can be initiated anywhere within the visual gaming area with any ship traffic configuration. The control station enables the researchers to interfere with the watch-standing crew on the bridge, to simulate malfunctions, and to control the operating mode of the

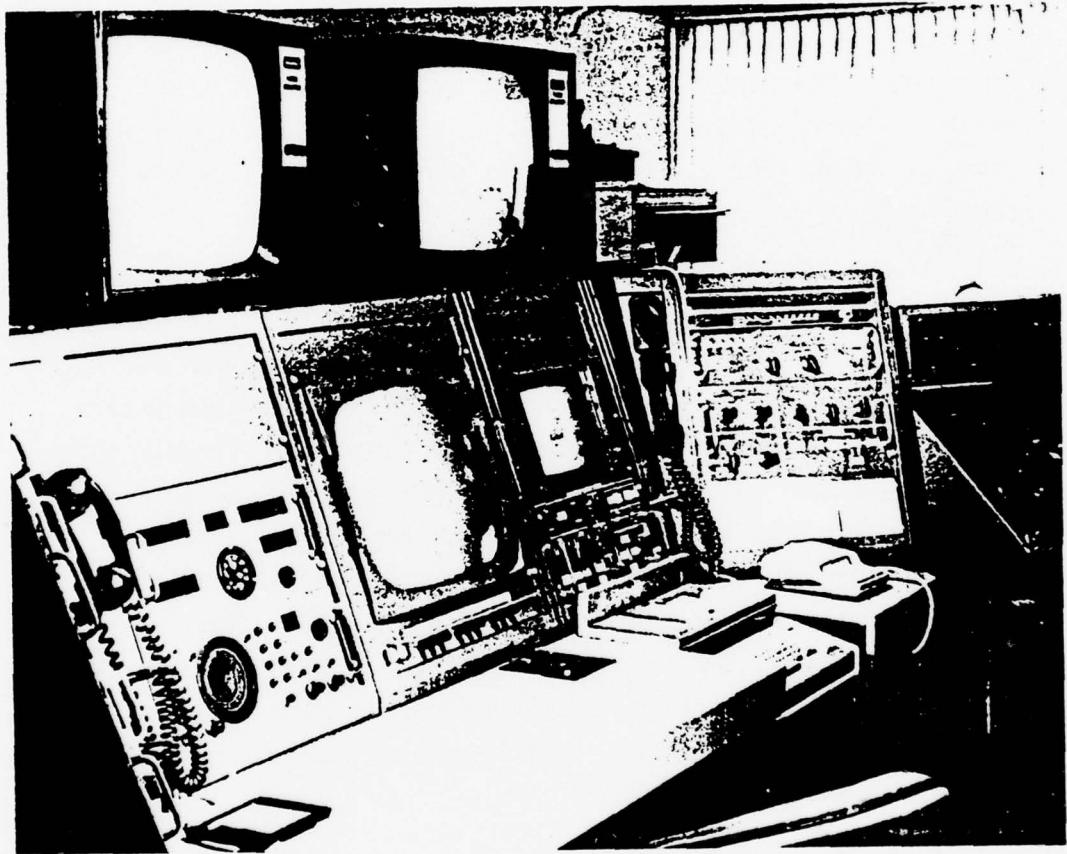


Figure C-4. Control Station

of the simulator. The Control Station is also capable of controlling motions of traffic ships and tugs in the gaming area and simulating telephone, intercom, radio (VHF, SSB) and whistle contact with the CAORF bridge crew.

C.1.6 HUMAN FACTORS MONITORING STATION

The Human Factors Monitoring Station (Figure C-5) is designed to allow collection of data on crew behavior. Monitoring data is provided by five closed-circuit TV cameras and four microphones strategically located throughout the wheelhouse to record all activities, comments and commands.

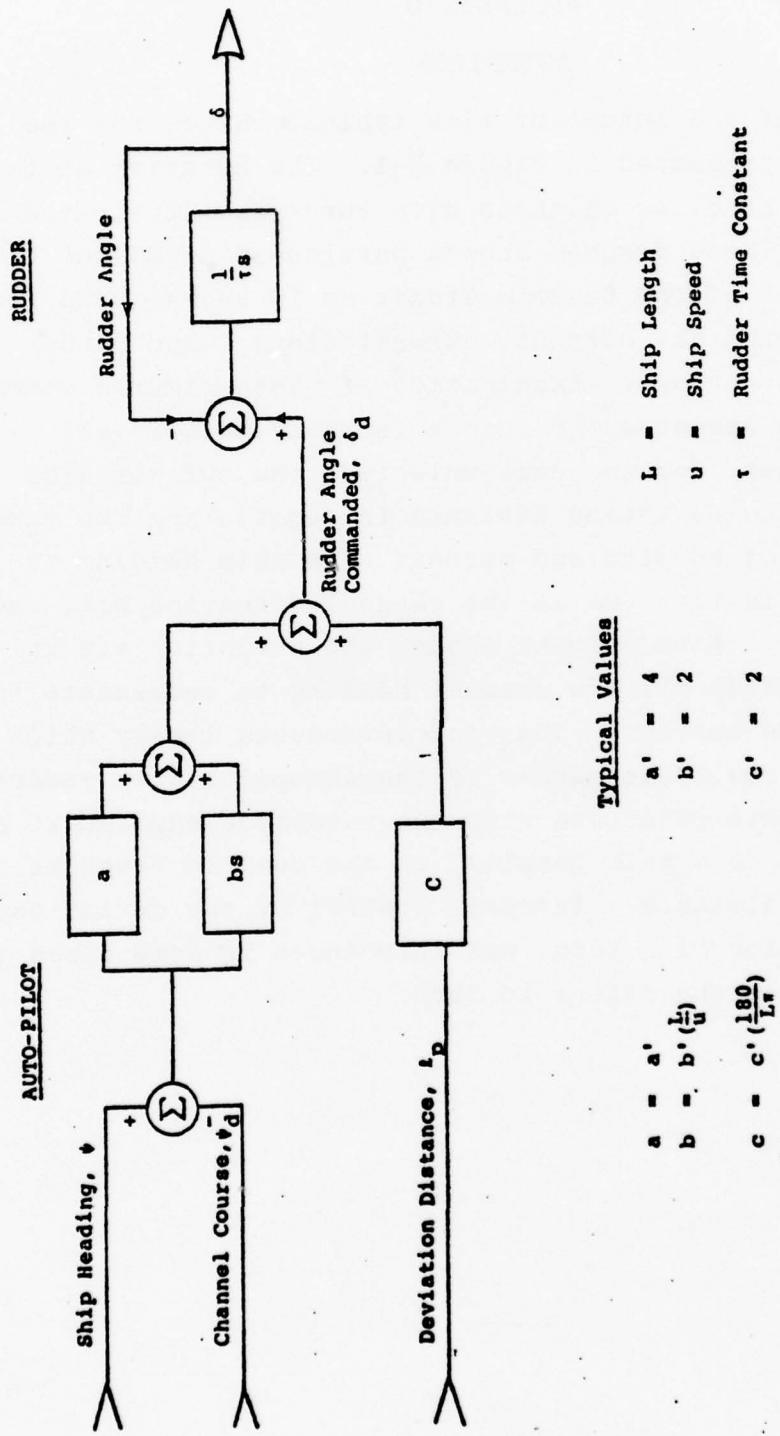


Figure C-5. Human Factors Monitoring Station.

APPENDIX D

AUTOPilot

A schematic of the autopilot with typical values for the constants is presented in Figure D-1. The behavior of this autopilot in handling channels with turns is illustrated in Figure D-2. These figures show a portion of an 80,000 DWT tanker transit of the Rosario Strait at 10 knots. The four runs are no wind and current, current alone, wind alone, and wind with current. Examination of these figures shows that the ship executes the turn reasonably well in all cases. In fact, for the case selected, the current aids in reducing the deviation distance in negotiating the turn. For the case of no wind and current, the ship heading in steady state is the same as the channel direction with rudder amidships. With current alone, the autopilot steers the ship slightly off the channel heading to compensate for the set of the current. The wind introduces leeway which is handled in a realistic manner by the autopilot with rudder. The steady-state condition with the autopilot exposed to a cross current is a path parallel to the desired track at a small offset distance. Integral control of the deviation, after completion of a turn, was introduced in some cases in order to reduce the effect to zero.



D-2

Figure D-1. Autopilot Schematic.

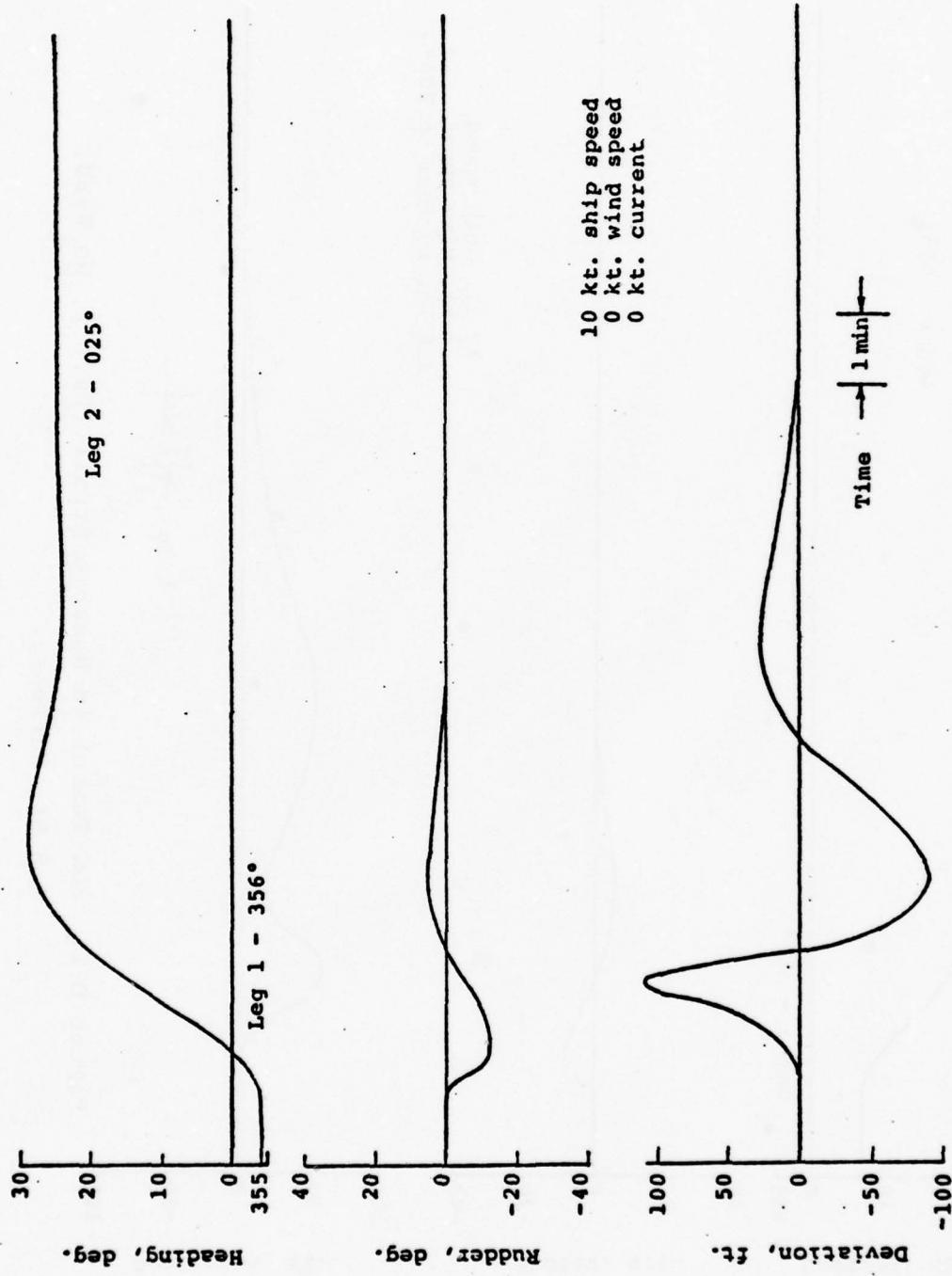


Figure D-2. 80K Tanker in Rosario Strait (Part 1, No Wind, No Current).

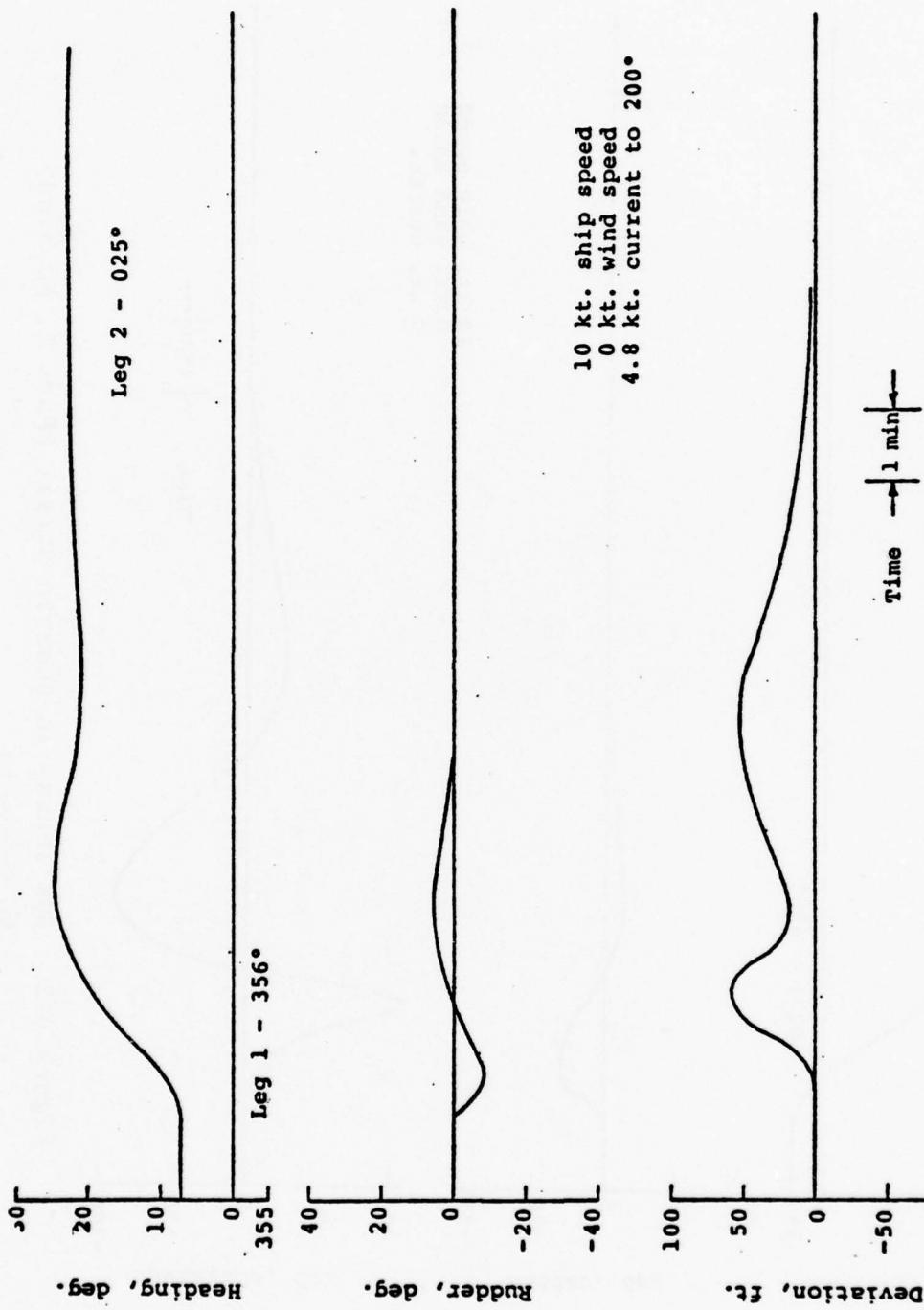


Figure D-2. 80K Tanker in Rosario Strait (Part 2, No Wind, 4.8 Kt. Current).

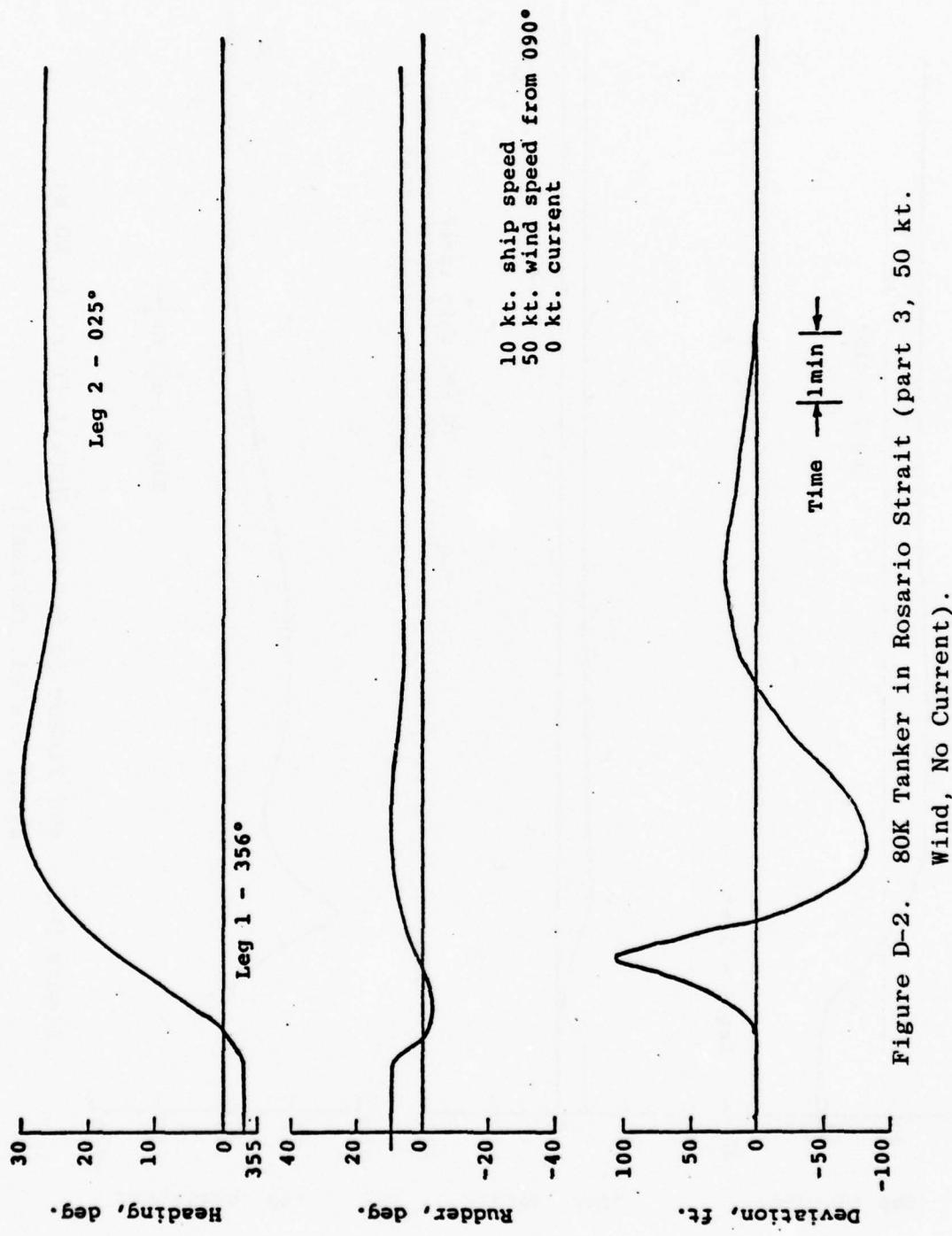


Figure D-2. 80K Tanker in Rosario Strait (part 3, 50 kt. Wind, No Current).

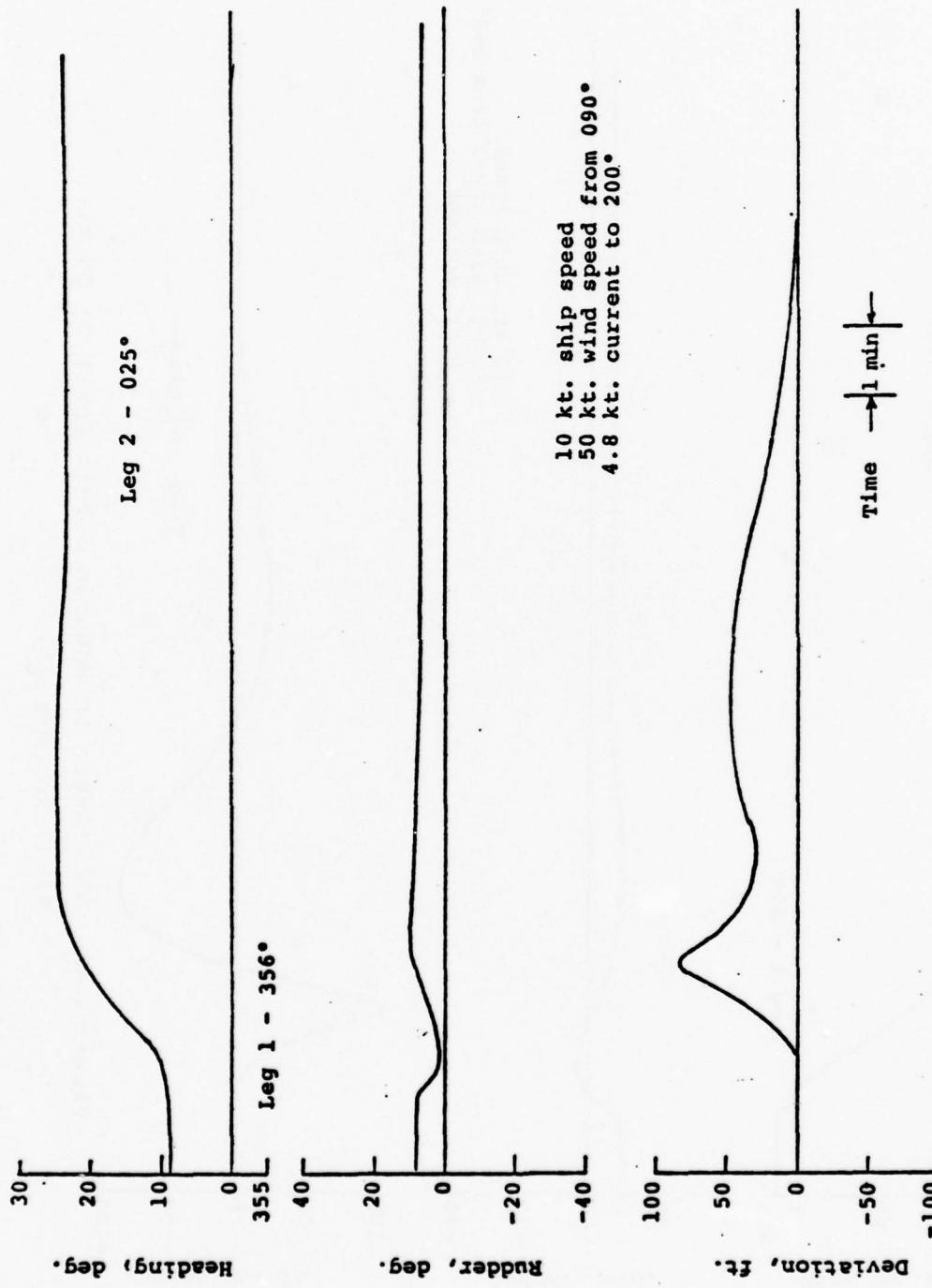


Figure D-2. 80K Tanker in Rosario Strait (Part 4, 50 kt.
Wind, 4.8 kt. Current).

APPENDIX E

MAN-IN-THE-LOOP SHIP GROUND TRACKS

This appendix contains the ground track of each of the piloted simulator runs. In all cases, the ship is the 165,000 DWT tanker and the plot frequency is once every 2 minutes. The conditions for each run are contained in the label in the upper right hand corner of the plot.

SHIP STABILITY PROGRAM - HIGHLIGHTS POINT

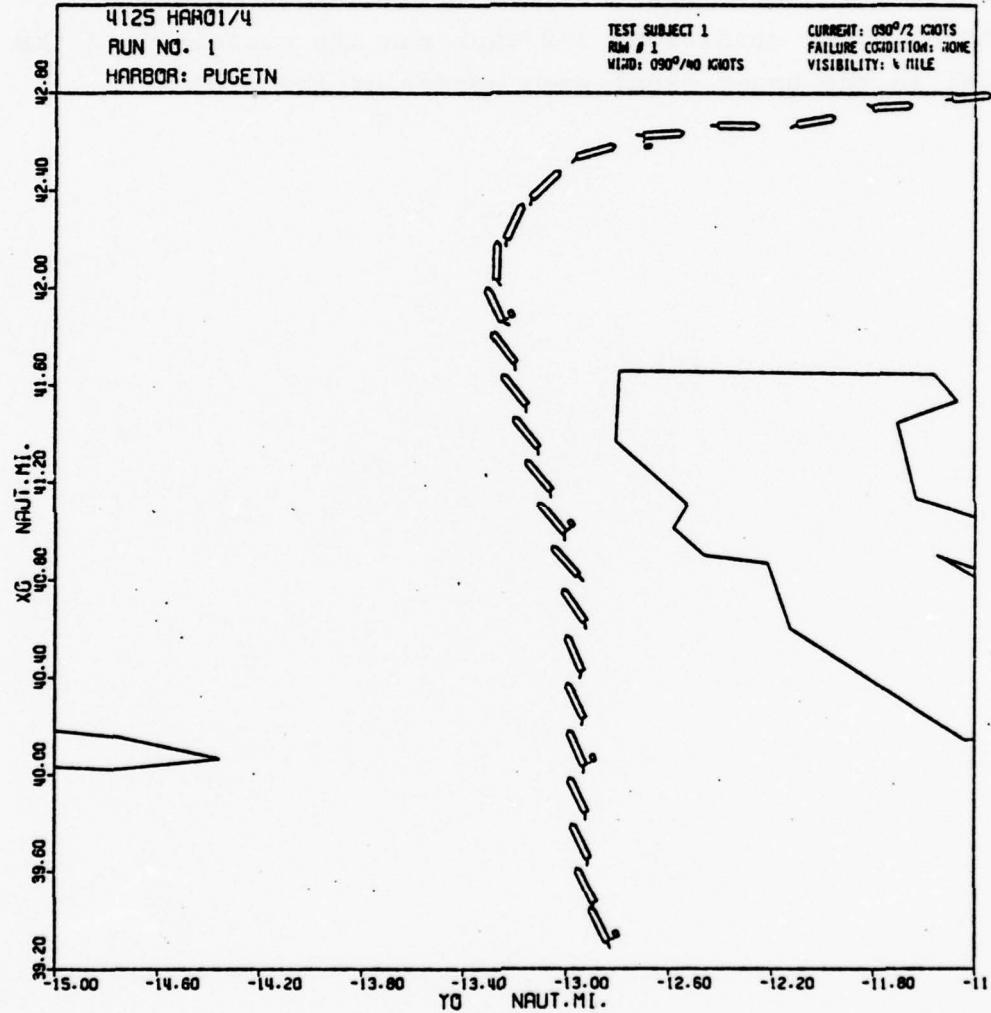
4125 HARB1/4

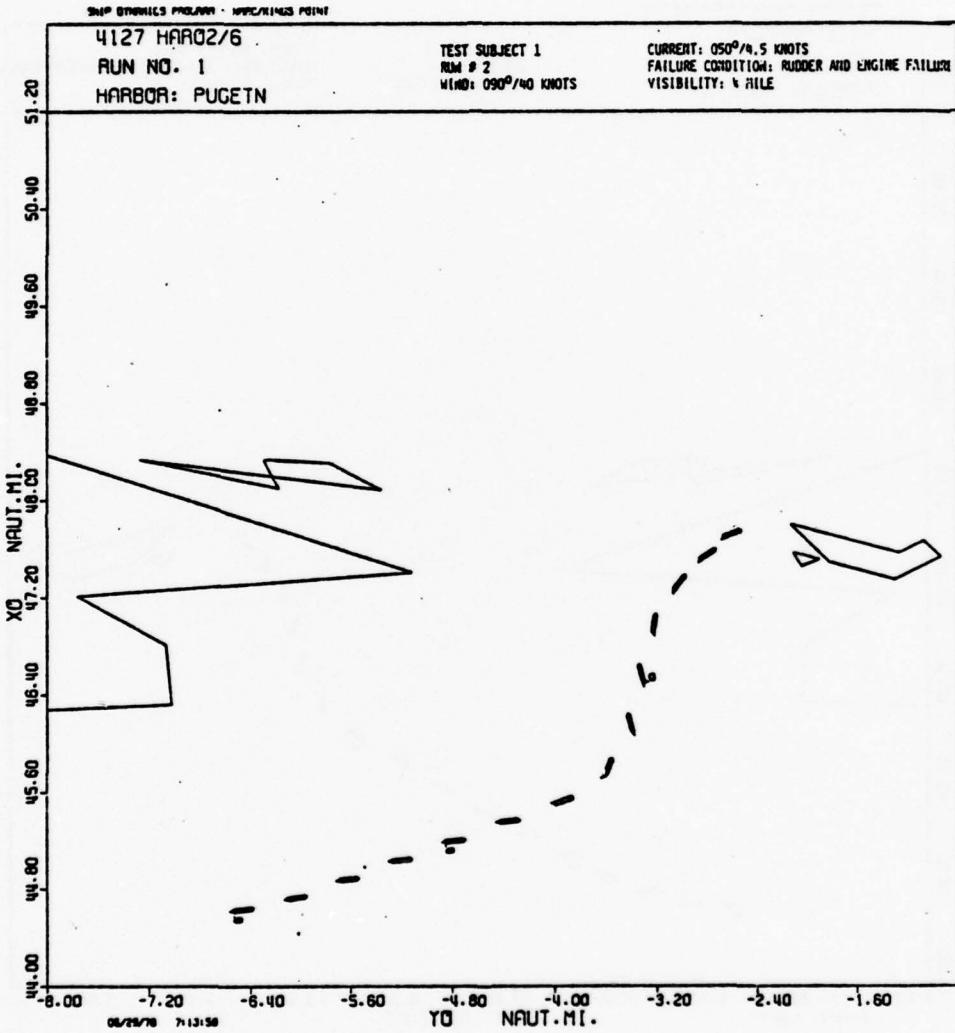
RUN NO. 1

HARBOR: PUGETN

TEST SUBJECT 1
RUN # 1
WIND: 090°/40 KNOTS

CURRENT: 090°/2 KNOTS
FAILURE CONDITION: NONE
VISIBILITY: 4 MILE





SHIP SIMULATIONS PROGRAM - HARBOR/POINT

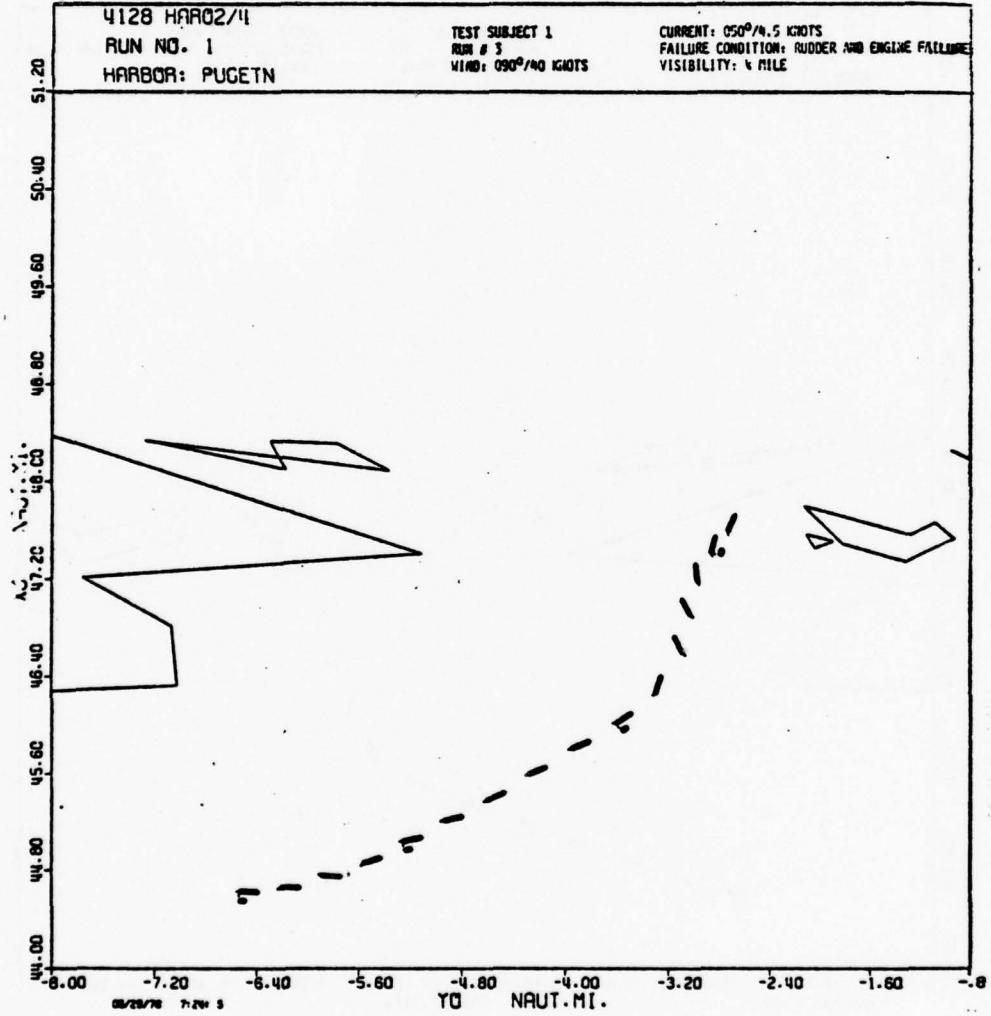
4128 HAR02/1

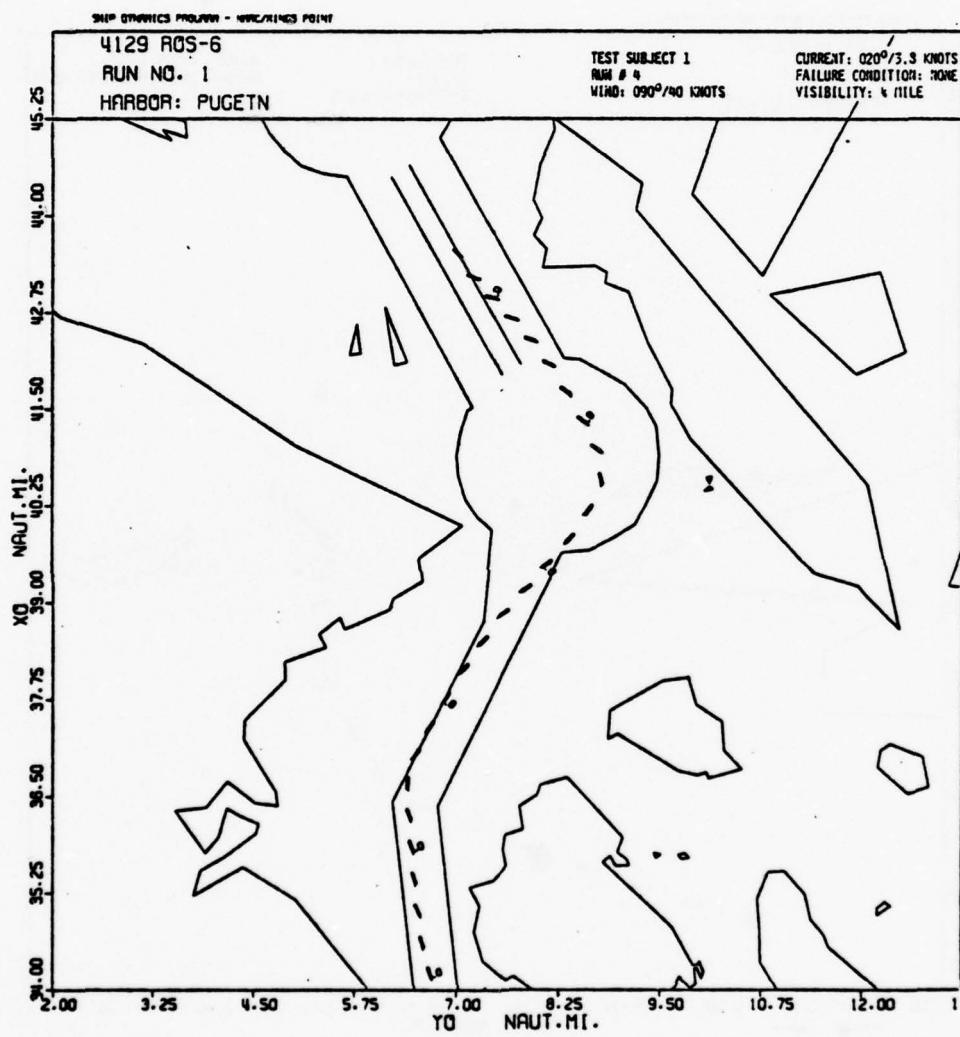
RUN NO. 1

HARBOR: PUGETN

TEST SUBJECT 1
RUN # 3
WIND: 090°/40 KNOTS

CURRENT: 050°/4.5 KNOTS
FAILURE CONDITION: RUDDER AND ENGINE FAILURE
VISIBILITY: 4 MILE



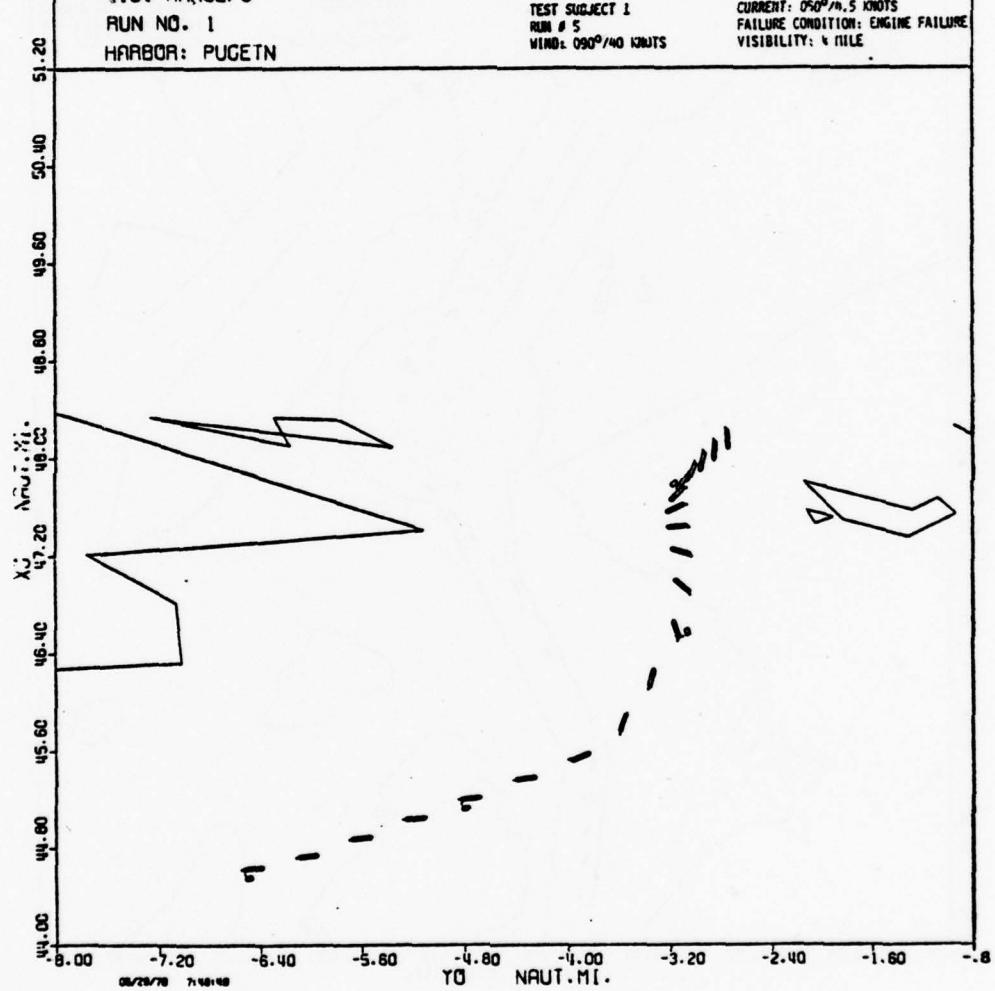


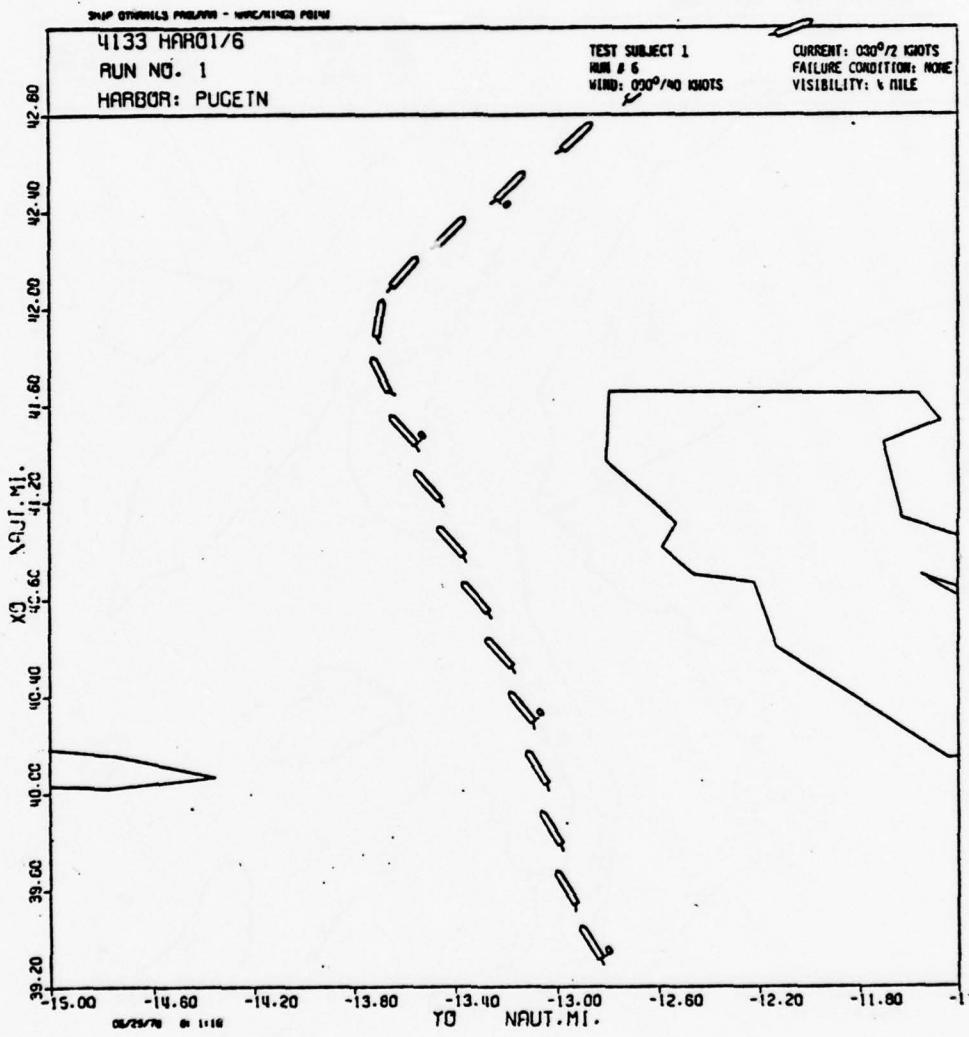
SHIP BREAKS PROGRAM - HIGHLIGHTS POINT

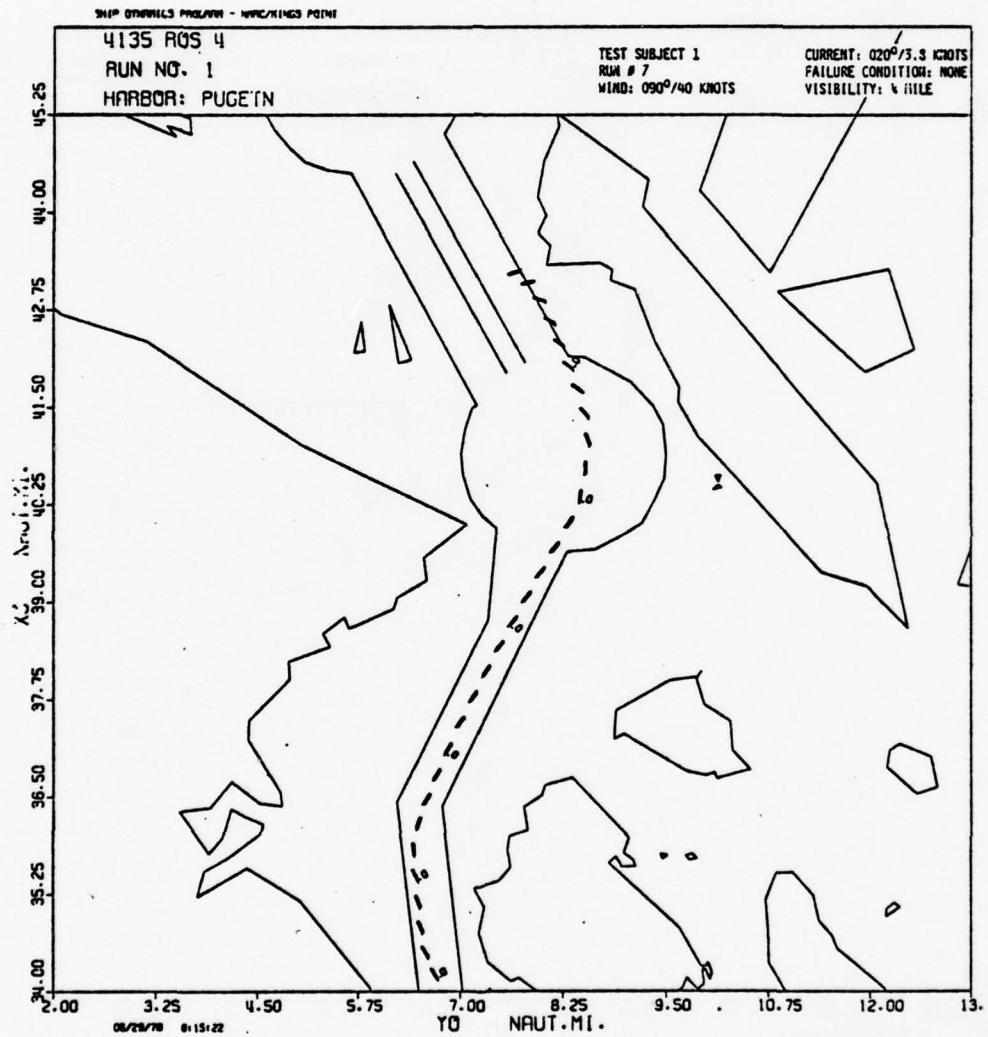
4131 HAR02/6

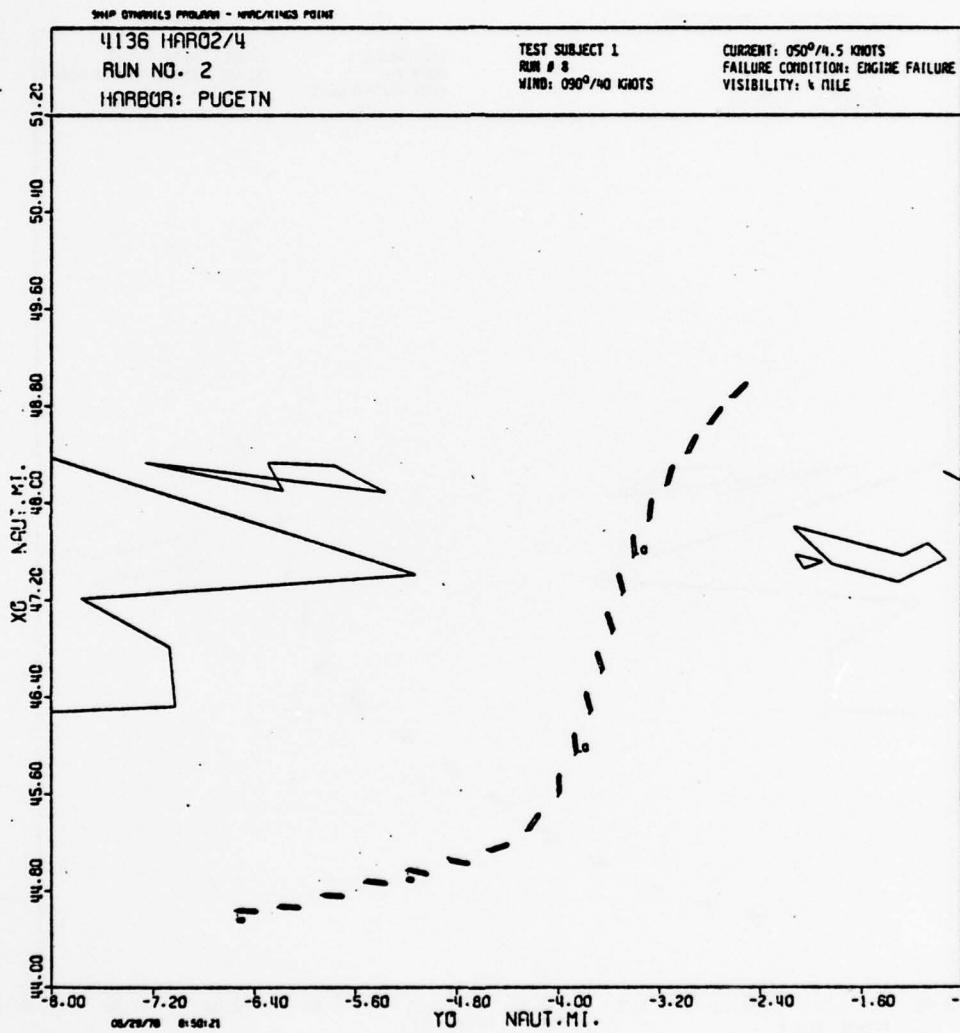
RUN NO. 1

HARBOR: PUGETN

TEST SUBJECT 1
RUN # 5
WIND: 090°/40 KNOTSCURRENT: 050°/0.5 KNOTS
FAILURE CONDITION: ENGINE FAILURE
VISIBILITY: 4 MILE







SHIP DYNAMICS PROGRAM - NAVIGATION POINT

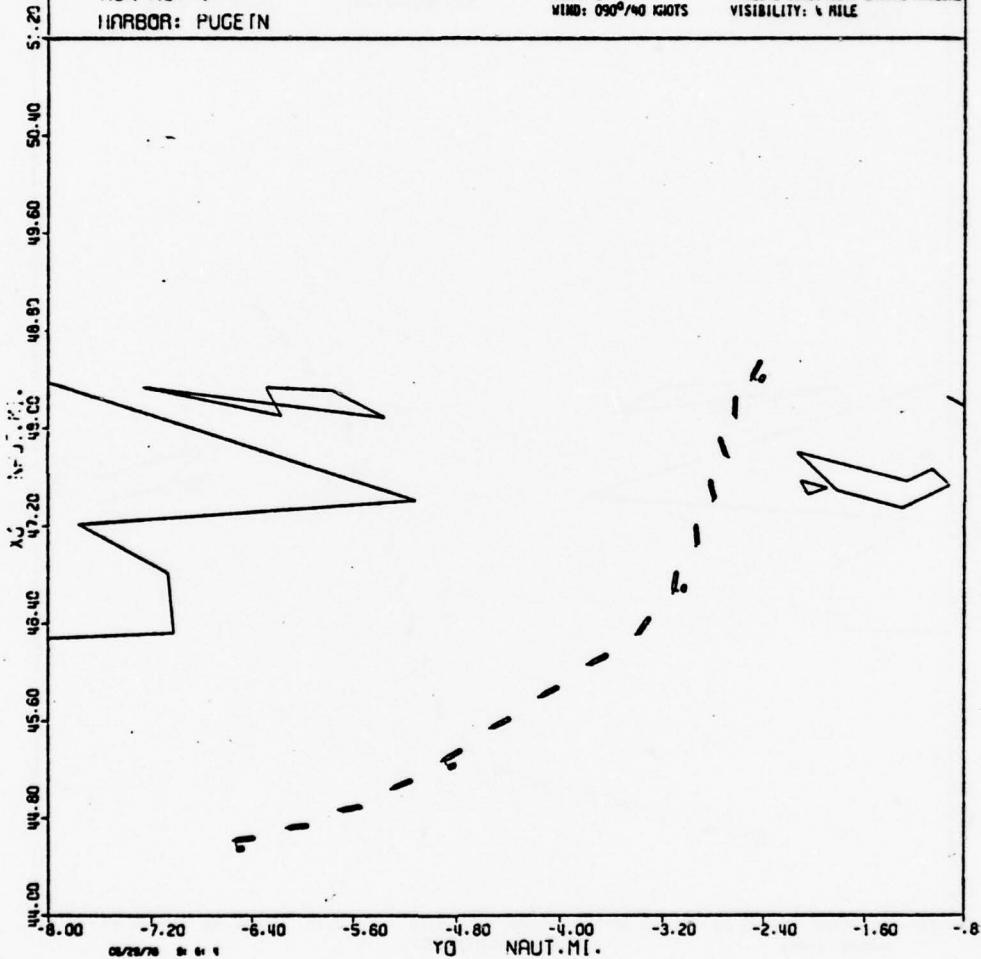
4130 HAR02/6

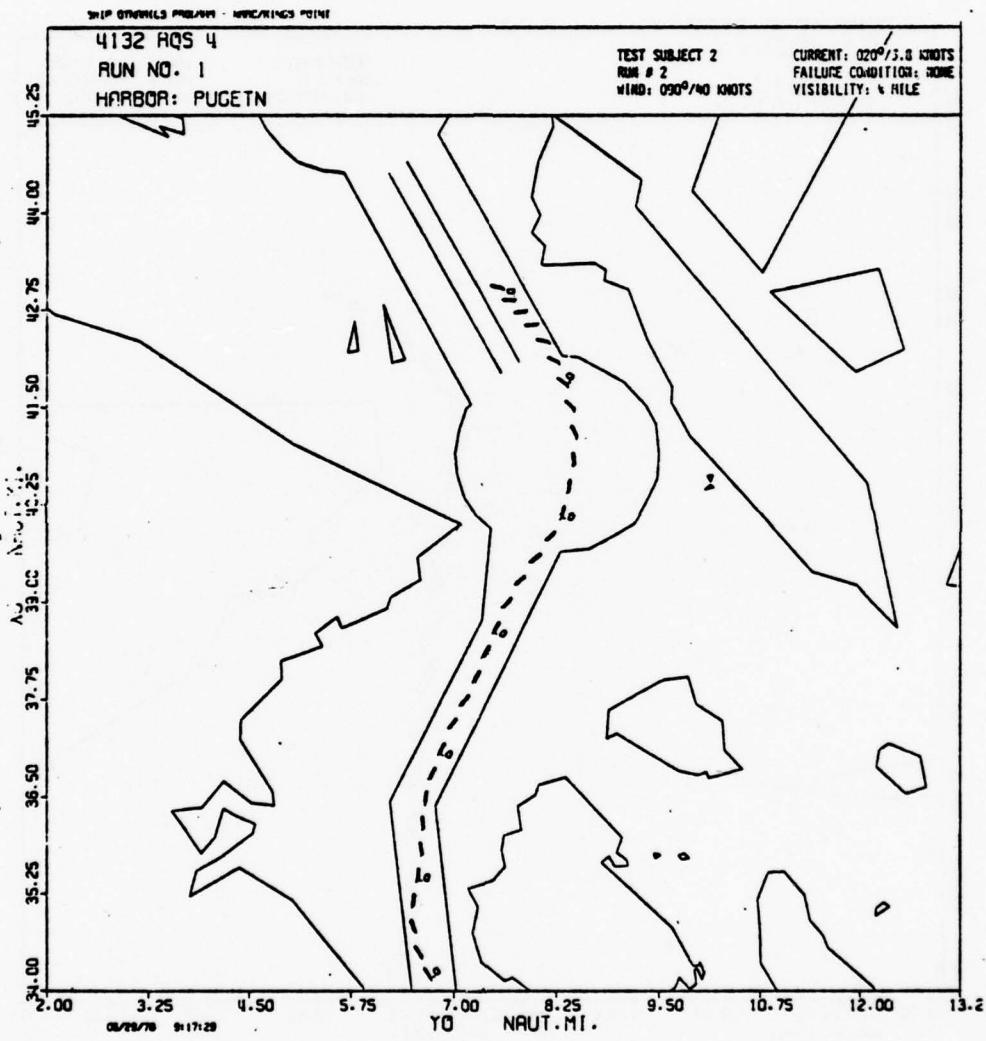
RUN NO. 1

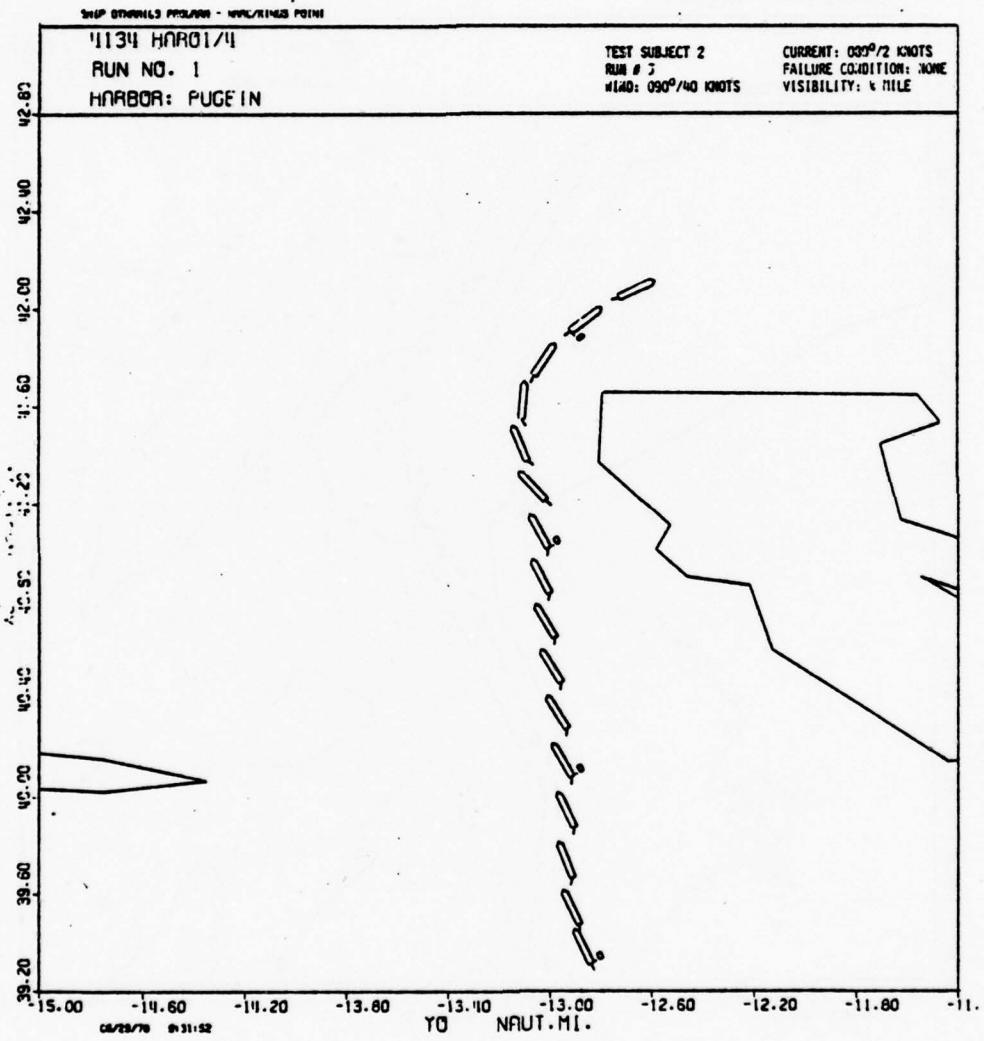
HARBOR: PUGET

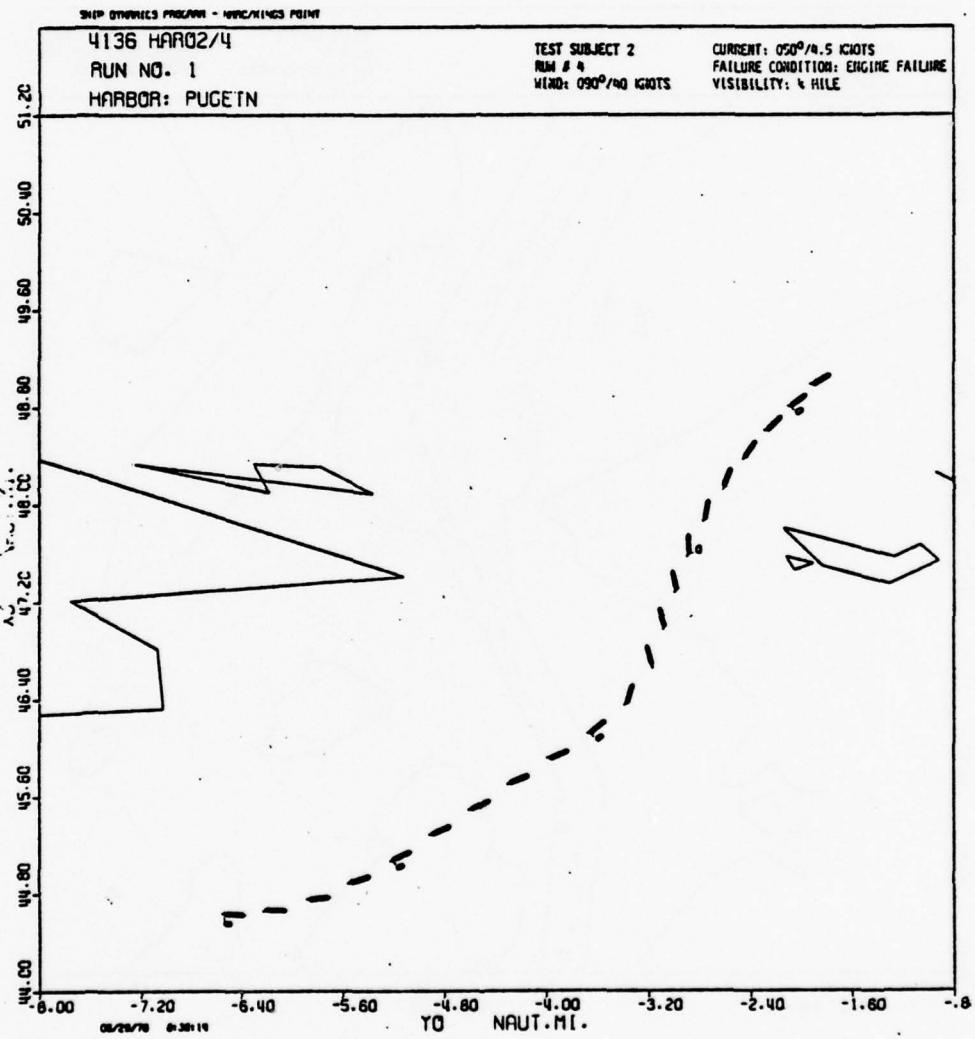
TEST SUBJECT 2
RUN # 1

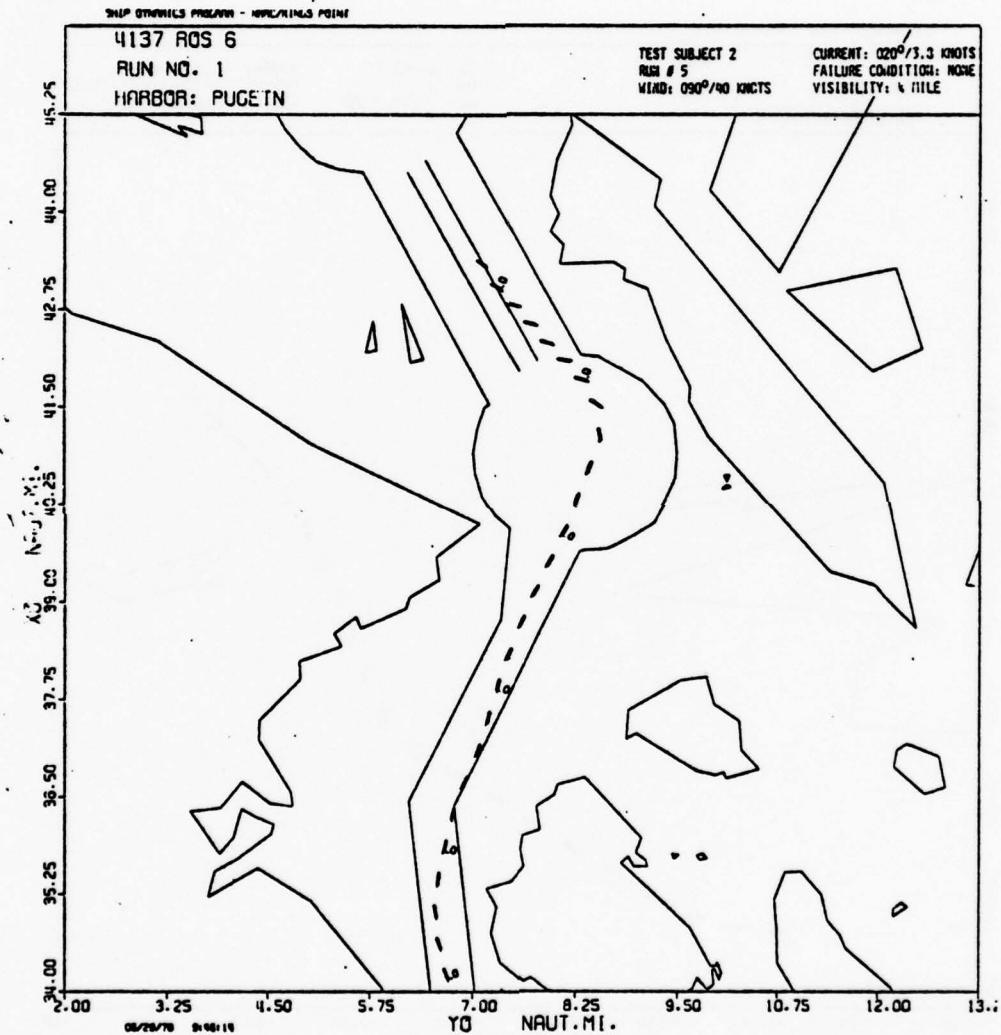
WIND: 090°/40 KNOTS

CURRENT: 050°/4.5 KNOTS
FAILURE CONDITION: ENGINE FAILURE
VISIBILITY: 4 MILE









SHIP SURVIVAL PROGRAM - NMIC/11403 POINT

4138 HAR02/6

RUN NO. 1

HARBOR: PUGETN

TEST SUBJECT 2

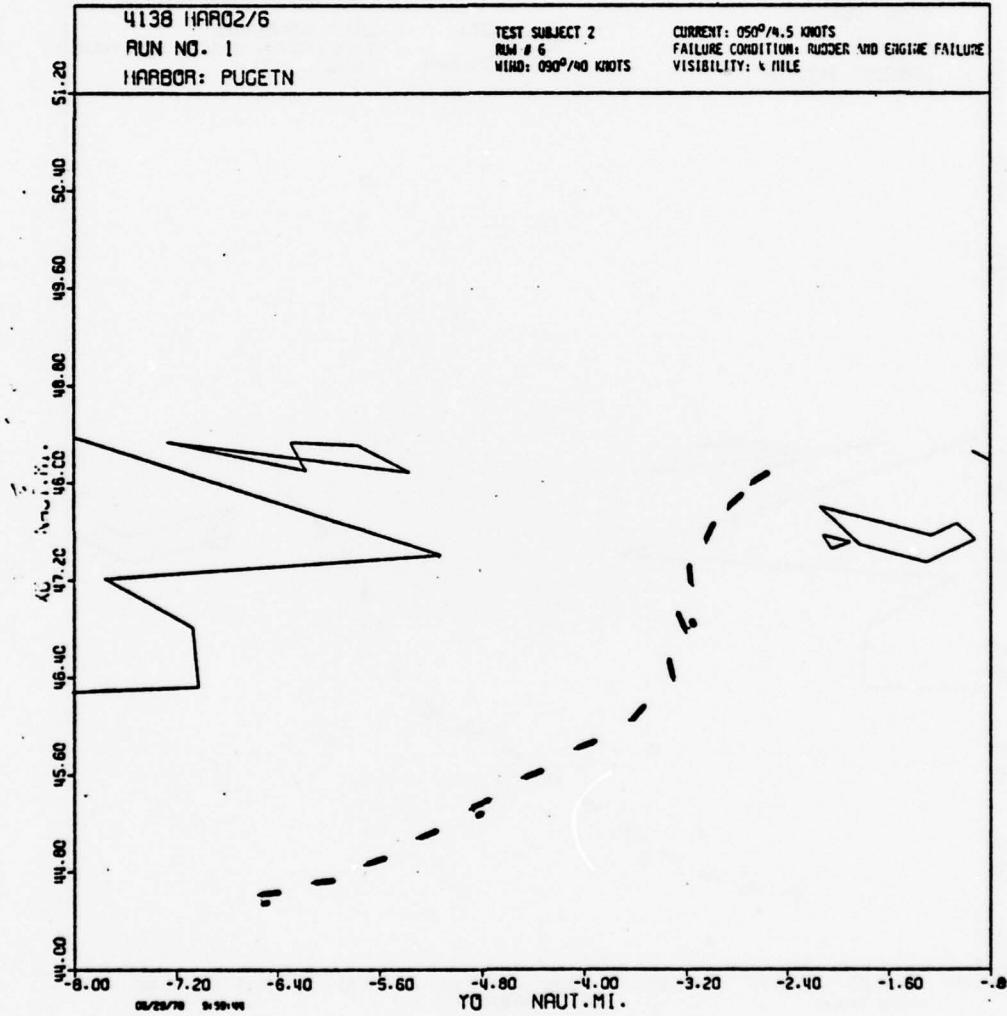
RIM # 6

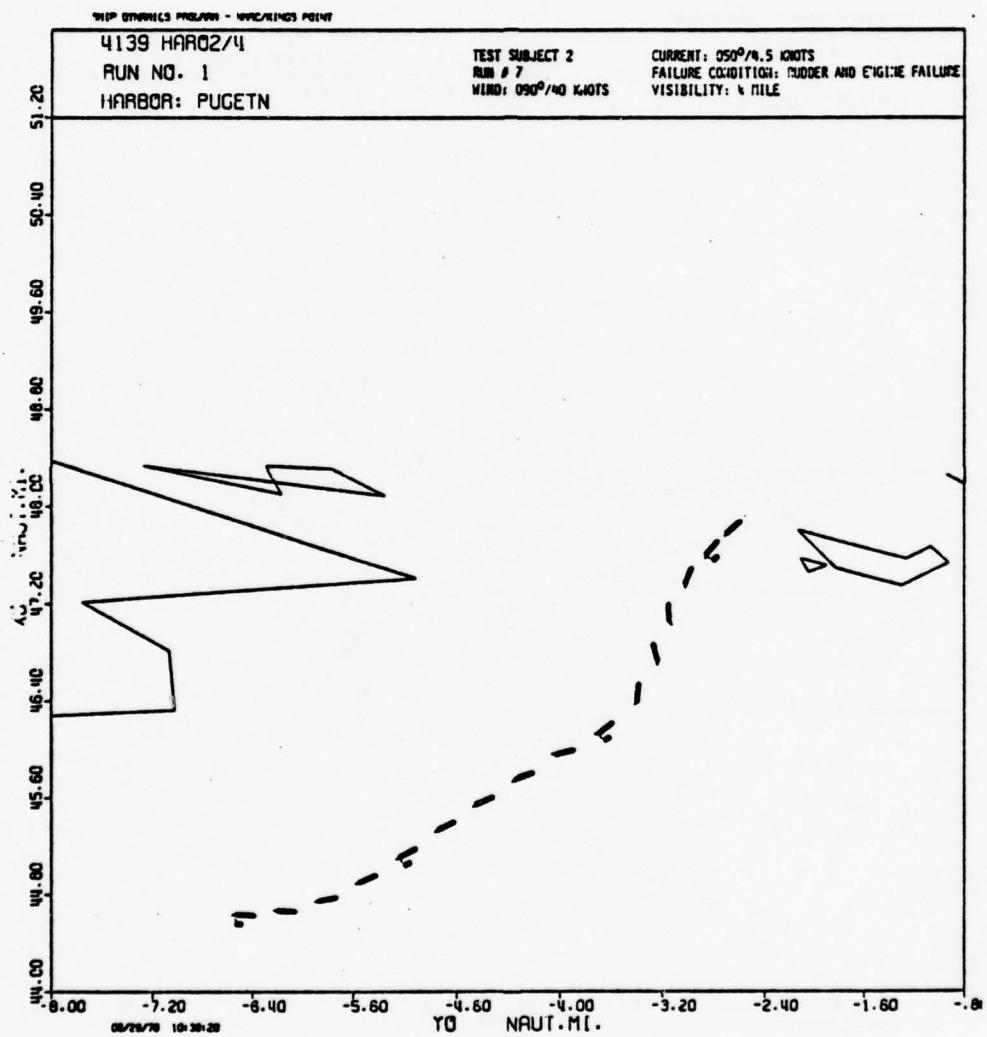
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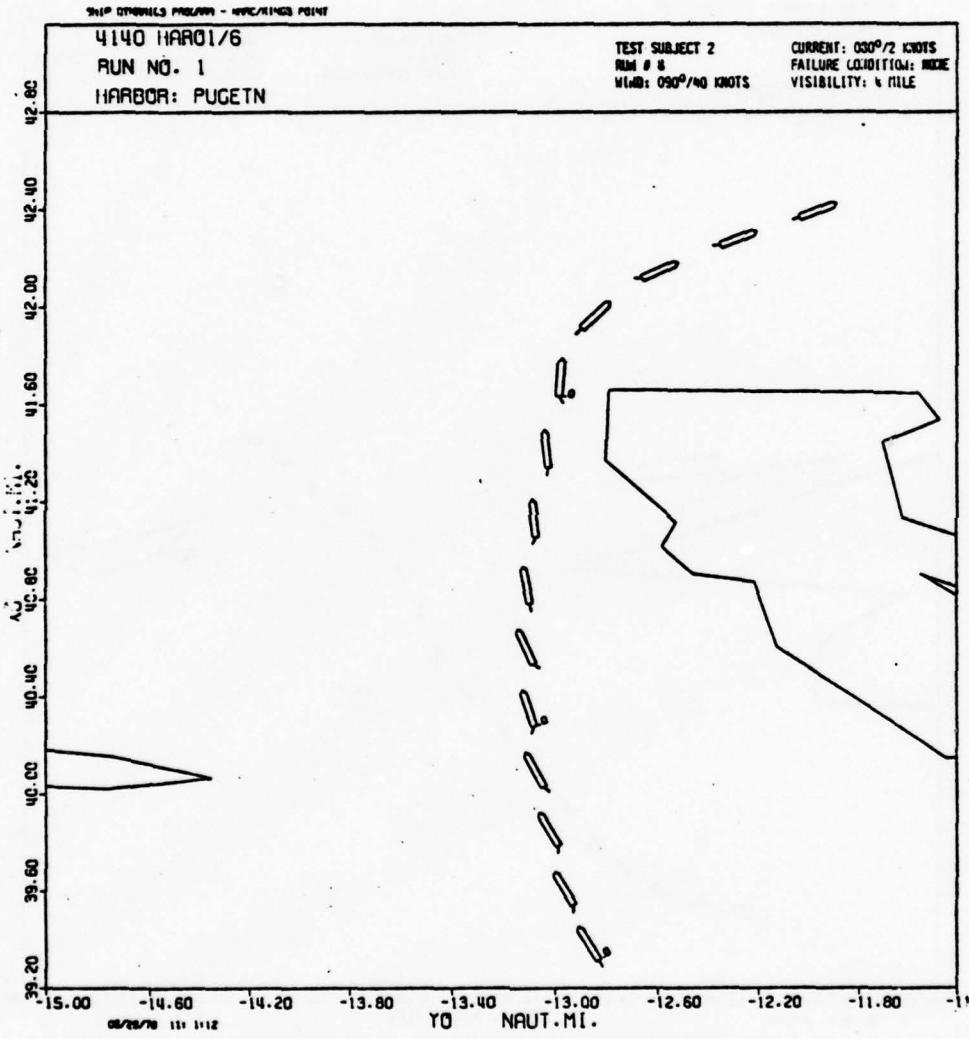
CURRENT: 050°/4.5 KNOTS

FAILURE CONDITION: RUDDER AND ENGINE FAILURE

VISIBILITY: 4 MILE







SHIP MANEUVERS PROGRAM - WMEC/RINGS POINT

4150 HAR02/4

RUN NO. 1

HARBOR: PUGETN

TEST SUBJECT 3

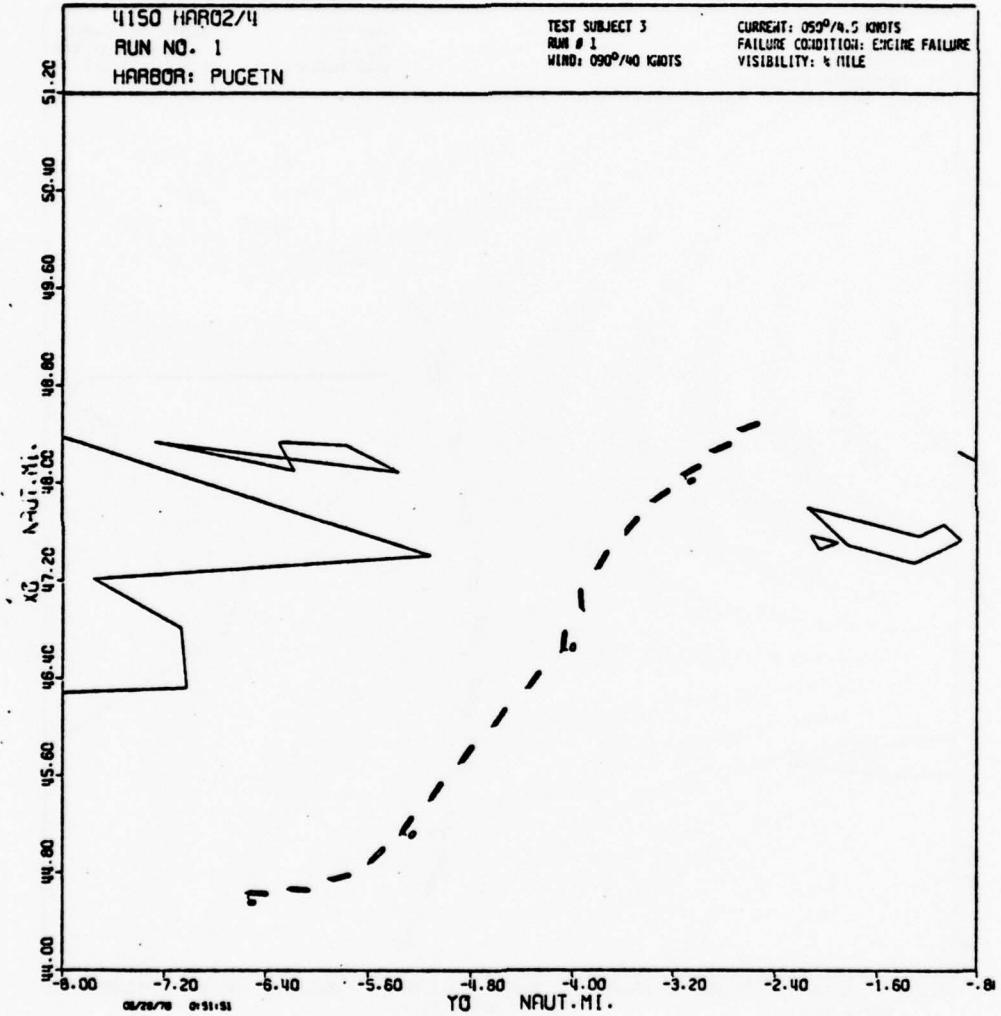
RUN # 1

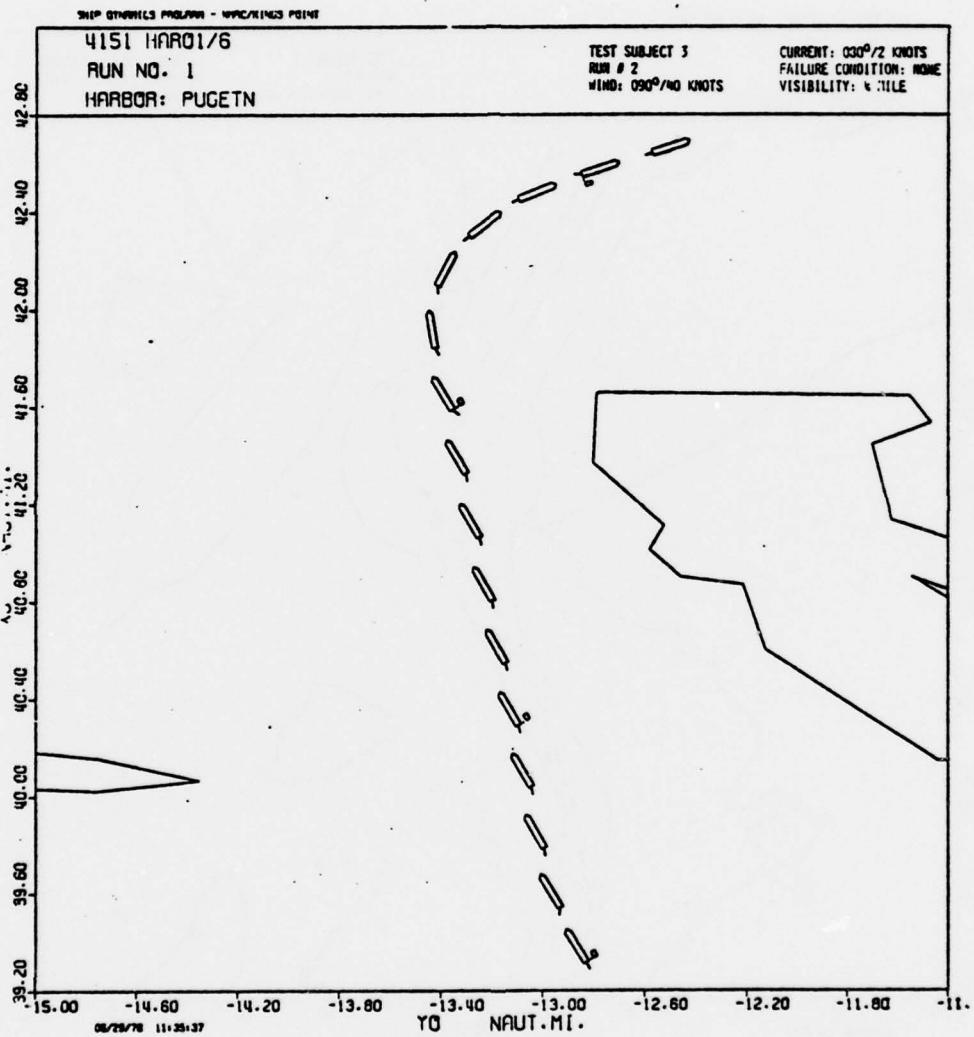
WIND: 090°/40 KNOTS

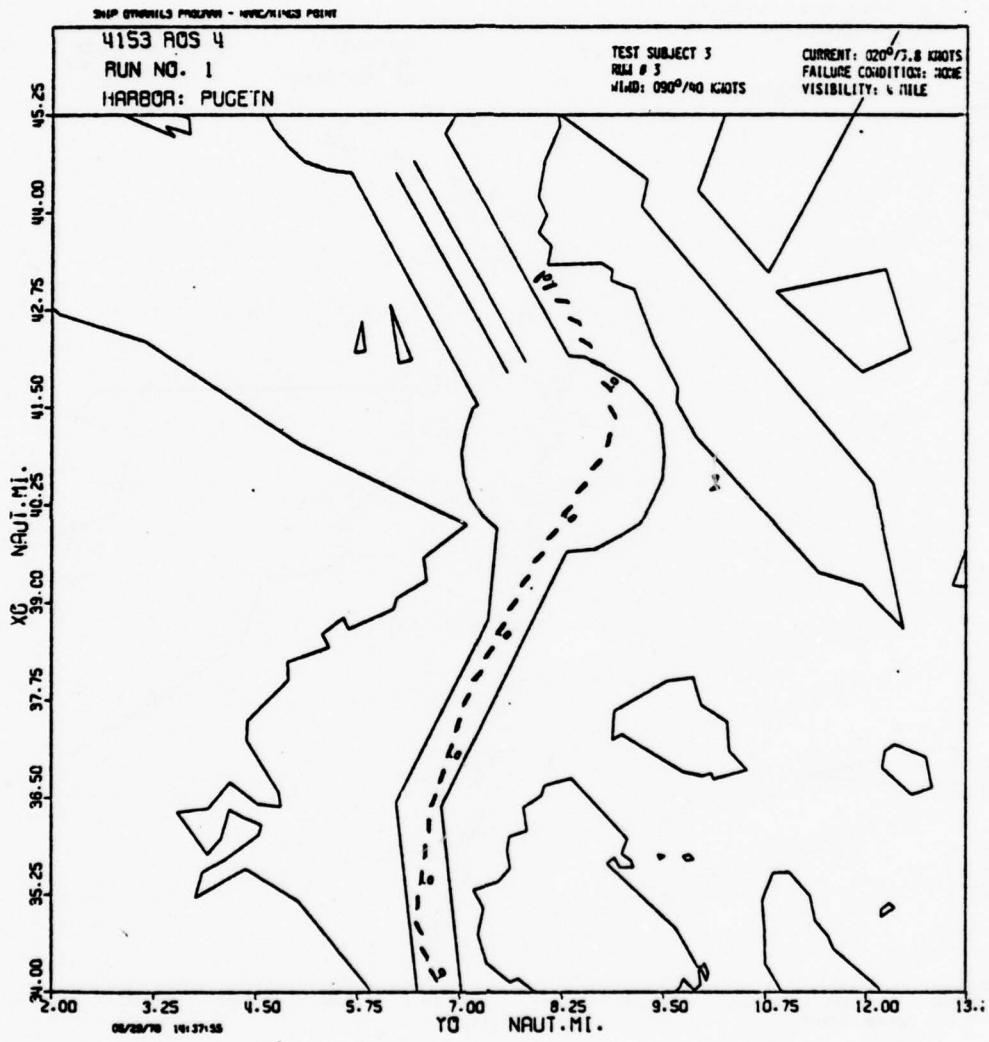
CURRENT: 050°/4.5 KNOTS

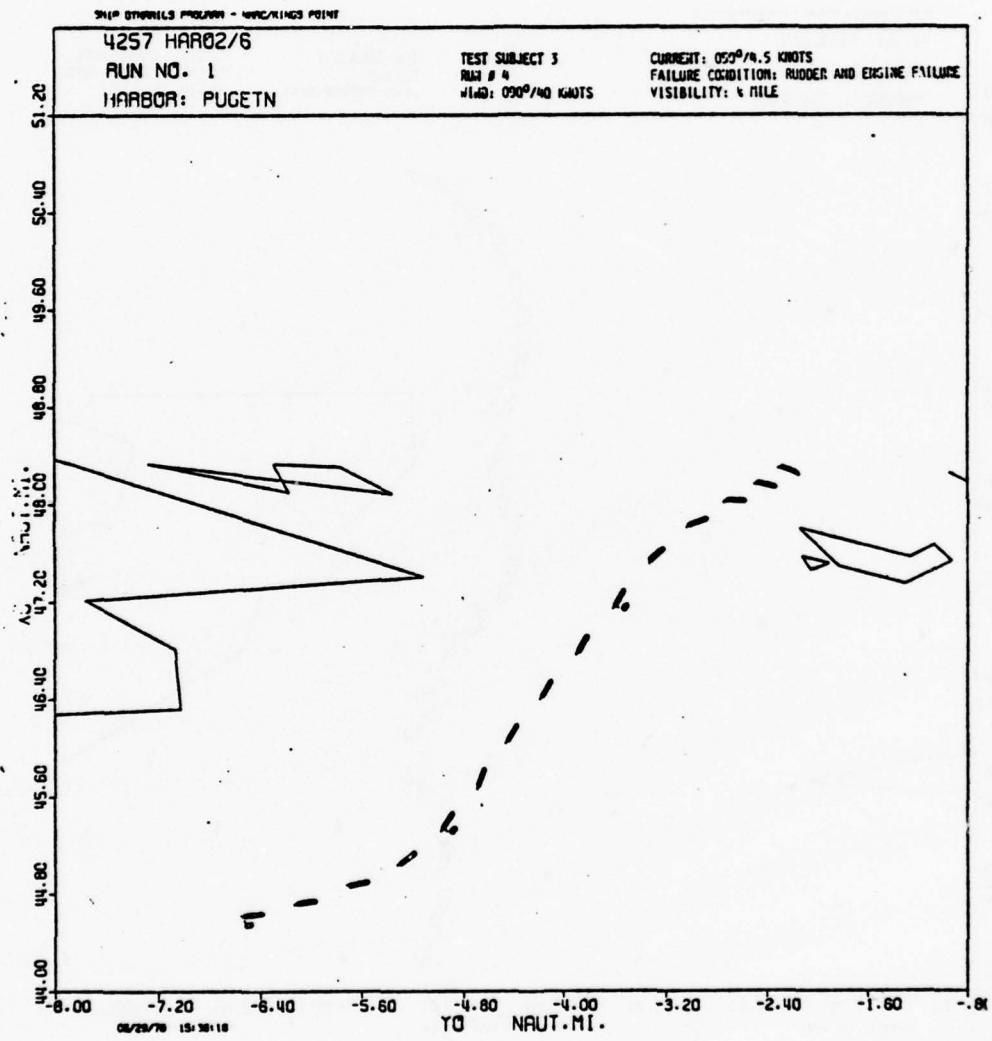
FAILURE CONDITION: ENGINE FAILURE

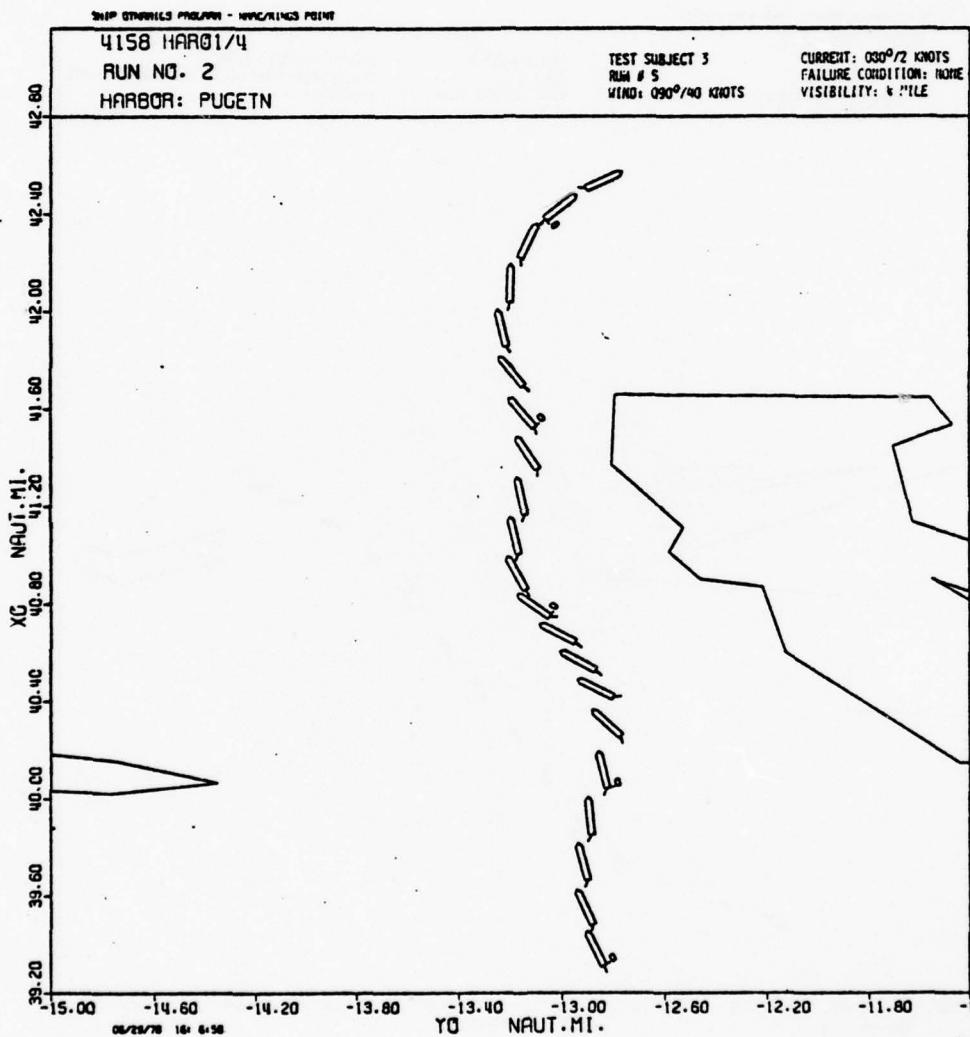
VISIBILITY: 1 MILE

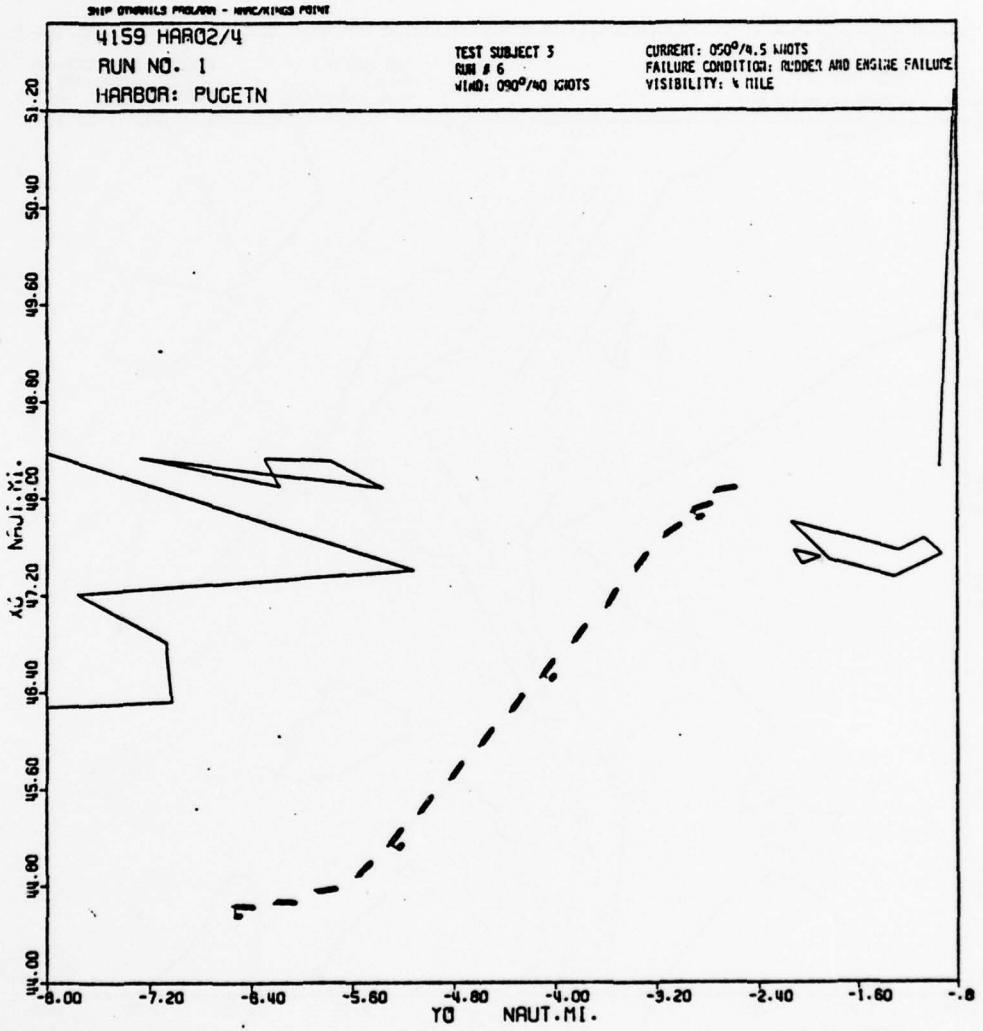


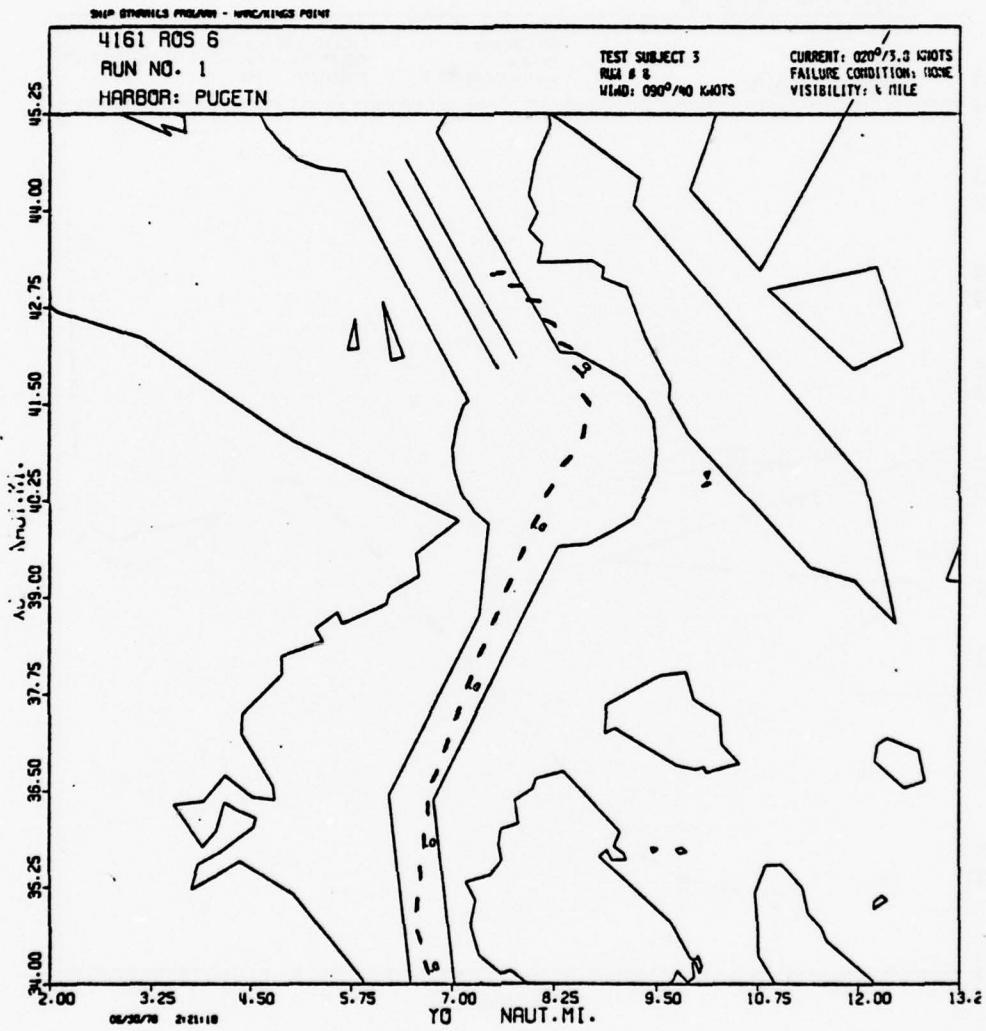


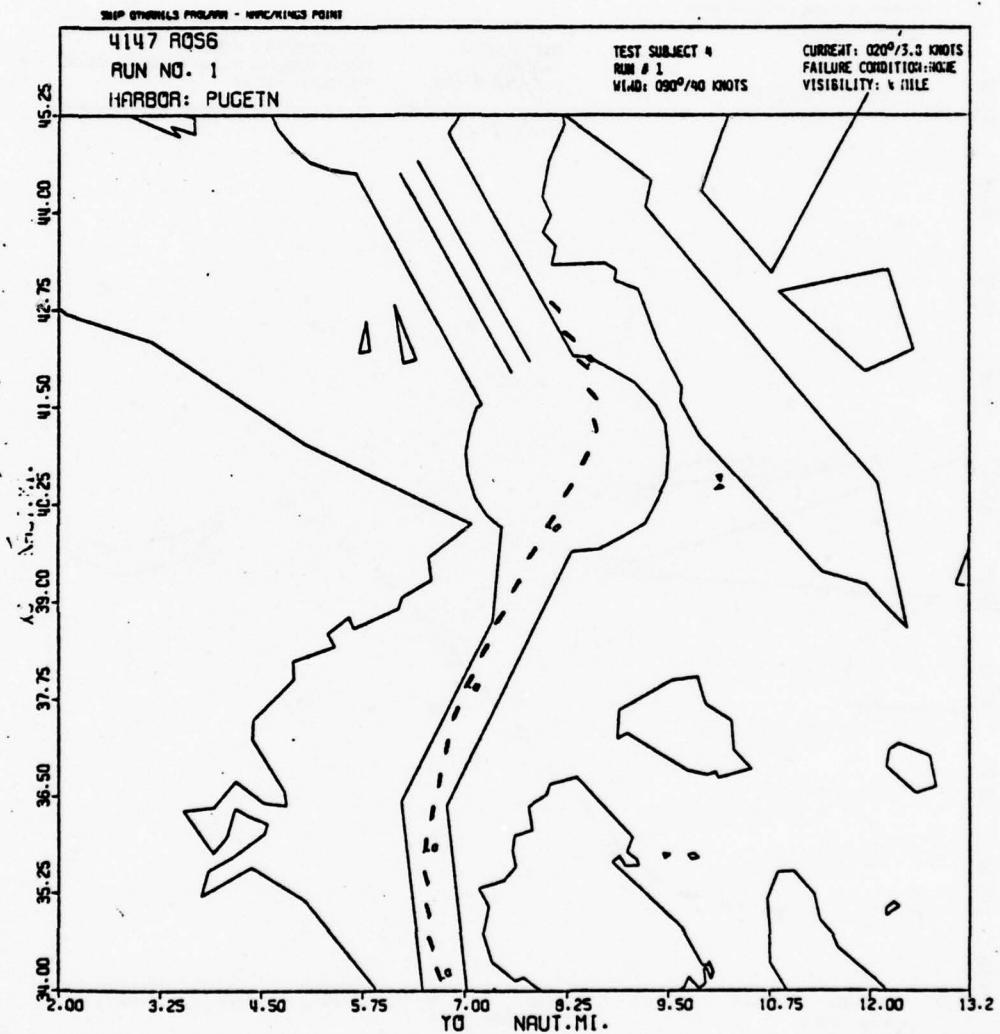


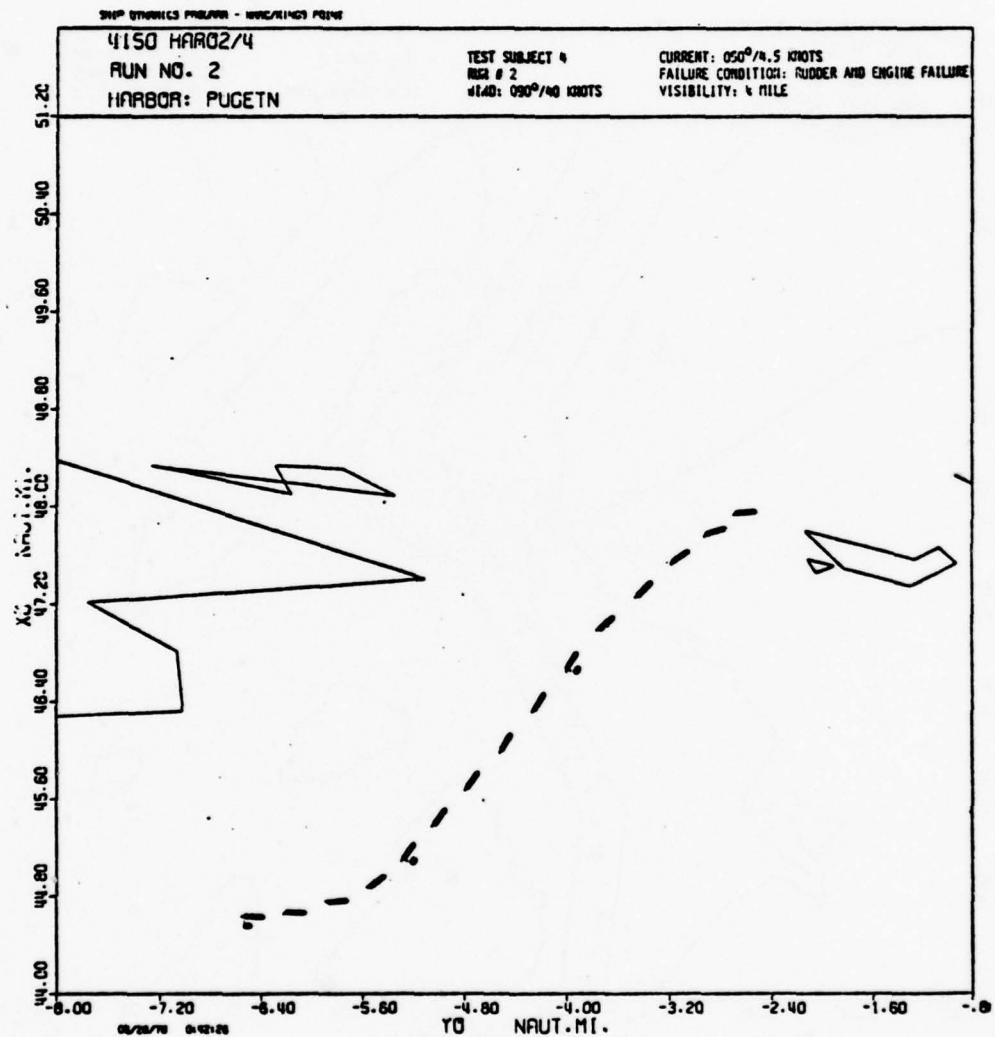


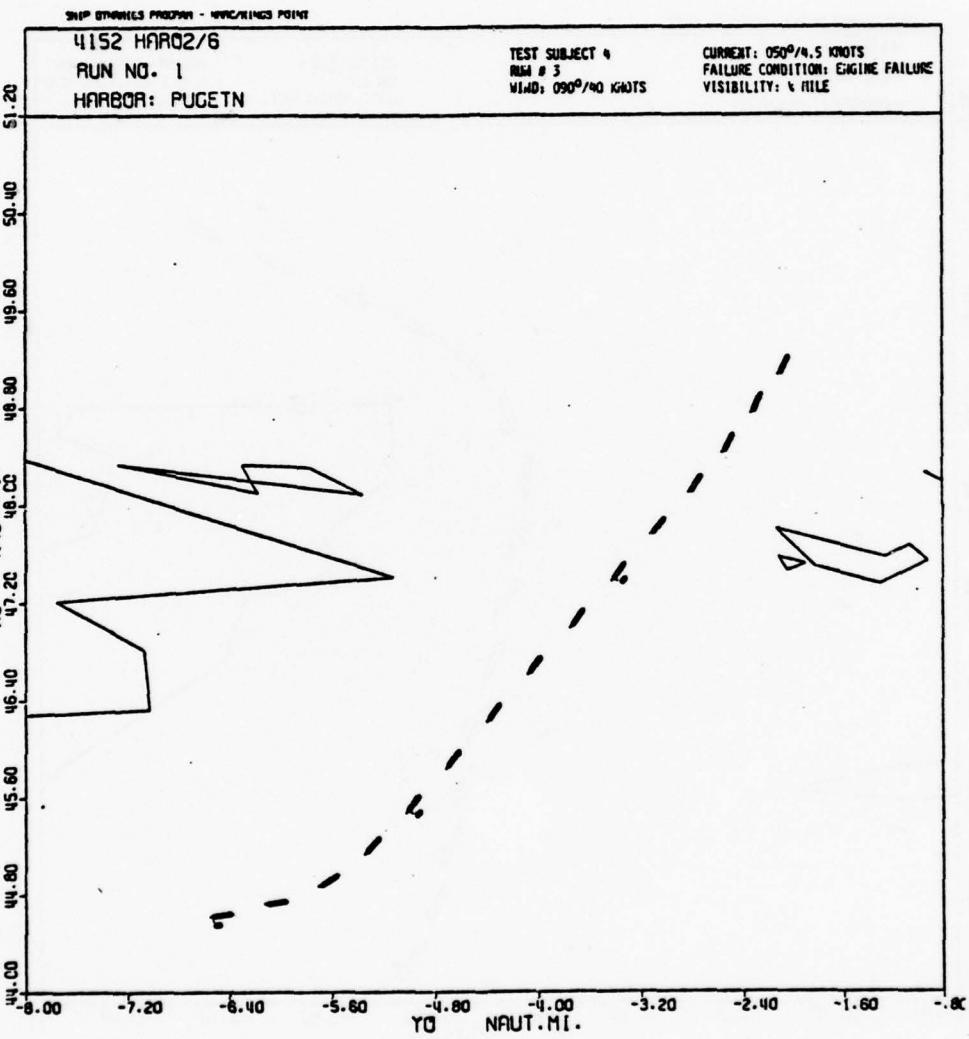


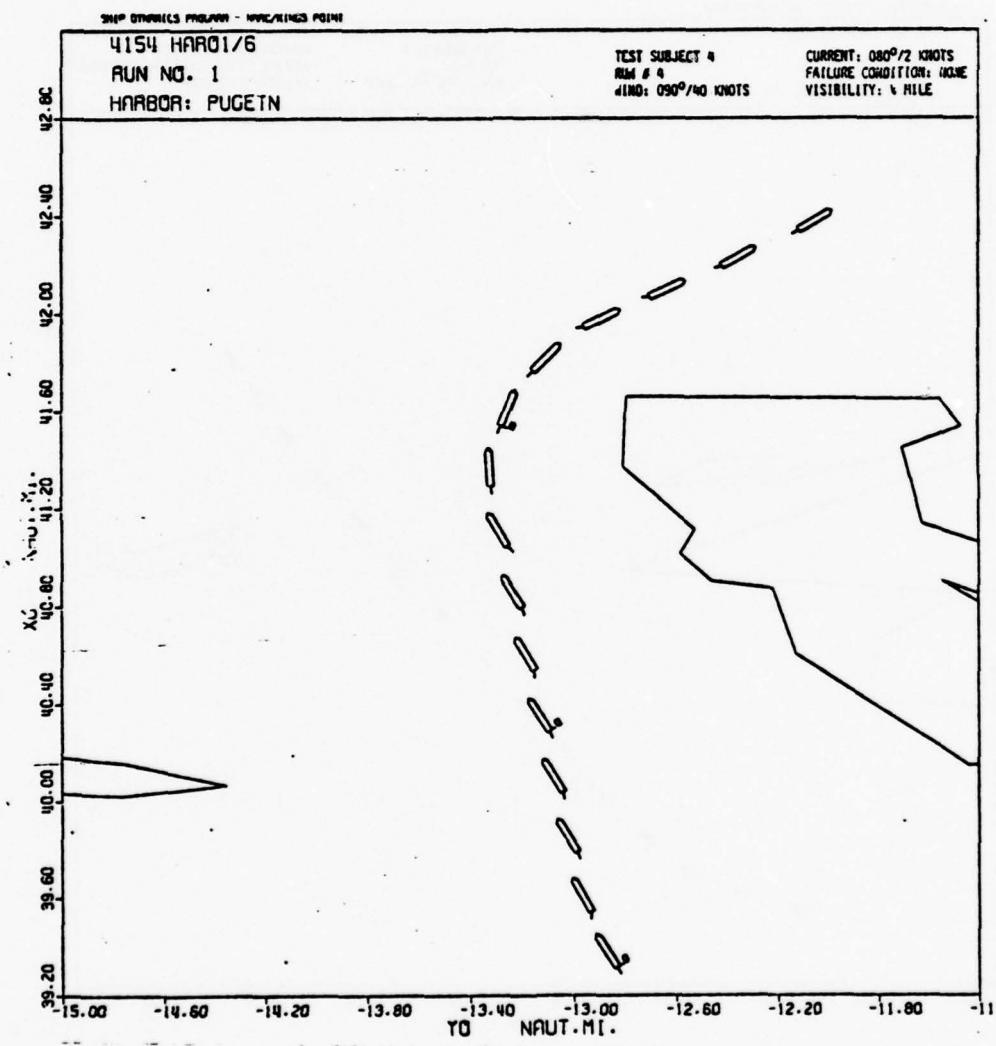


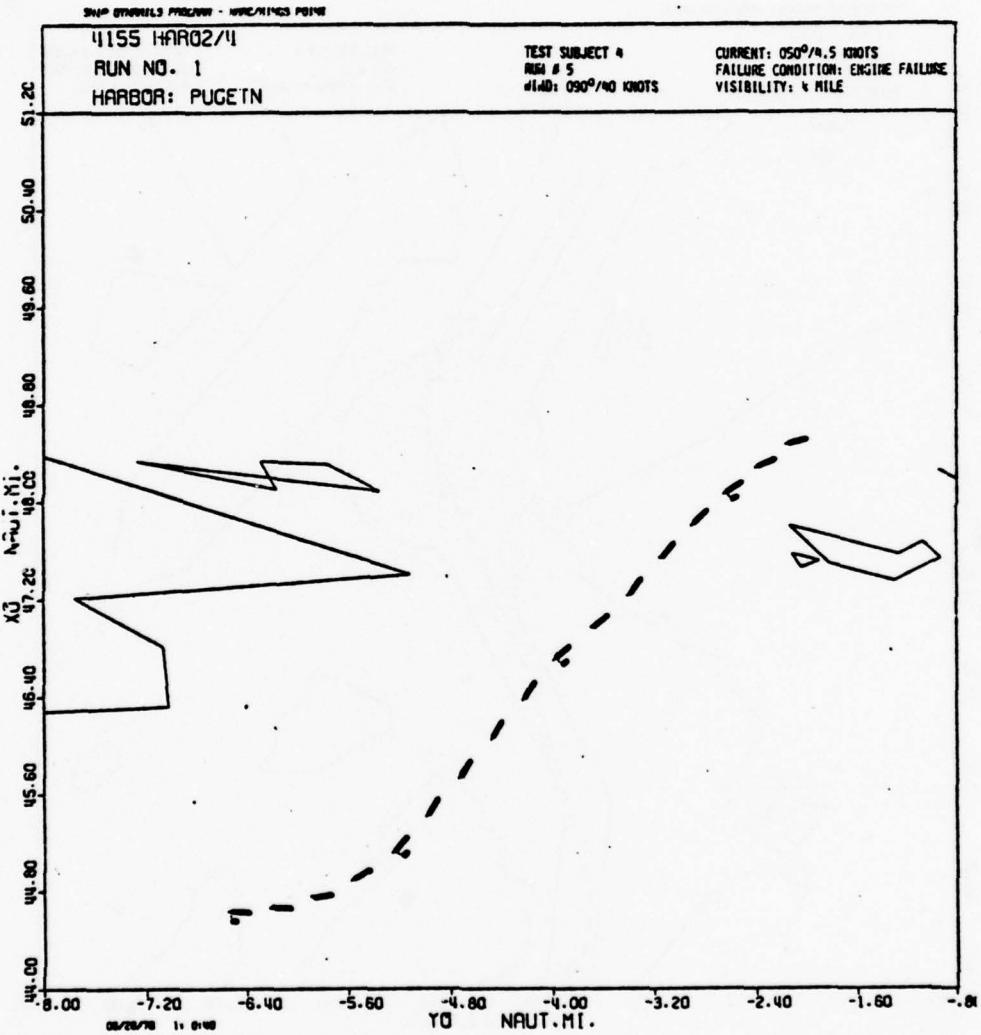


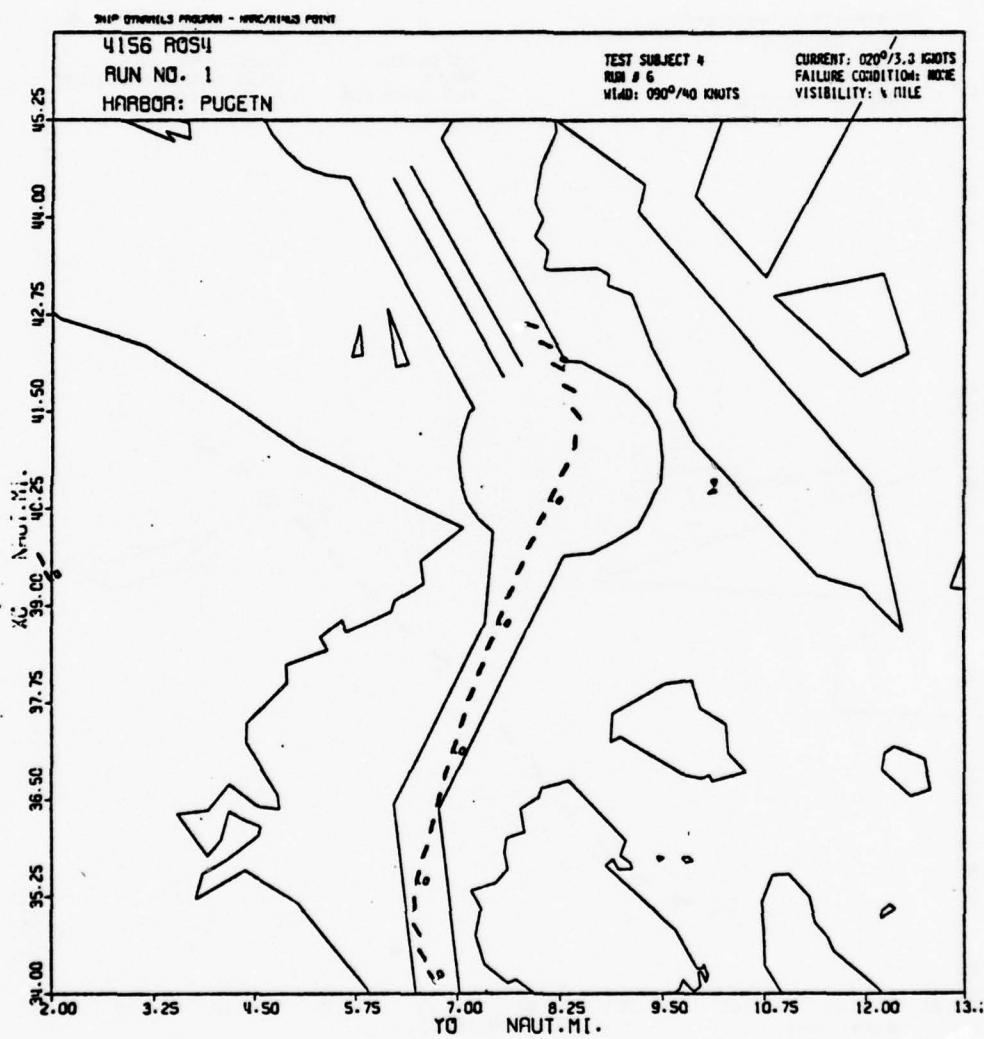


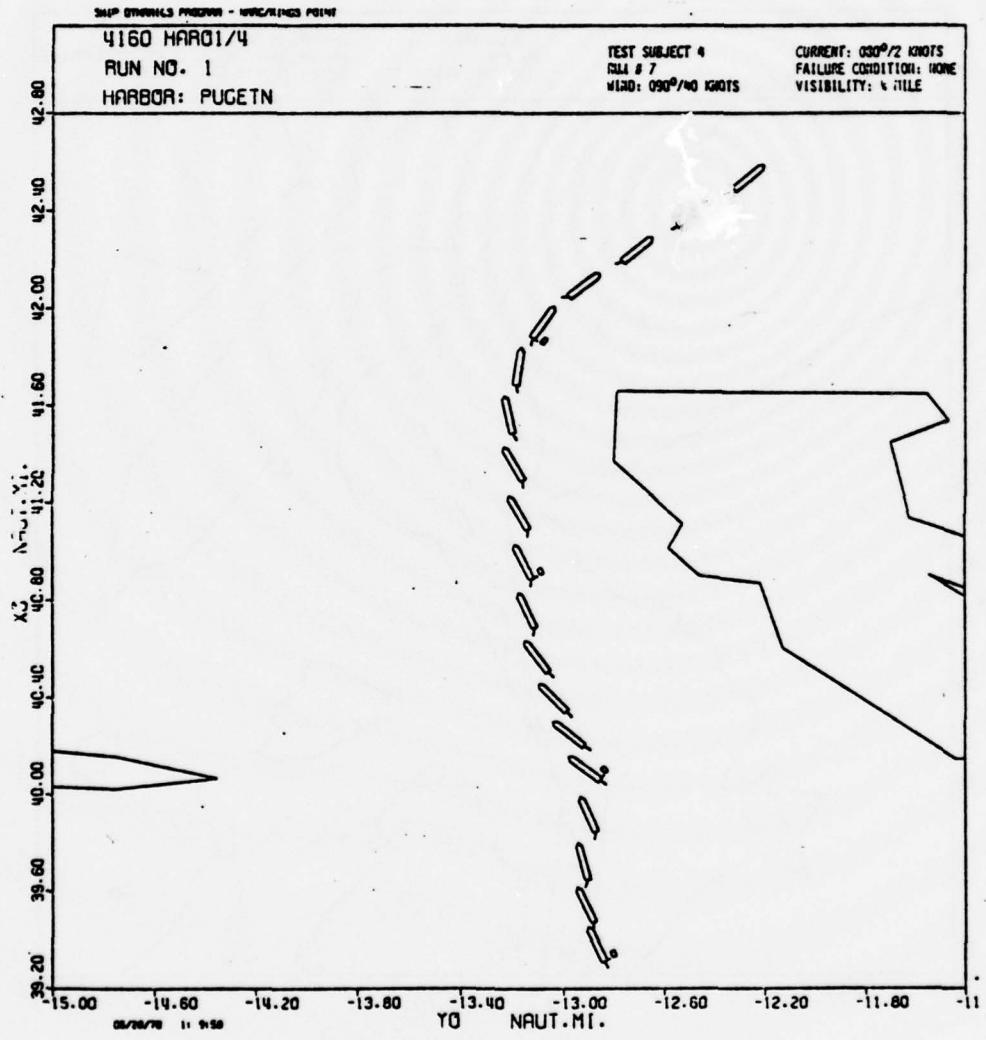


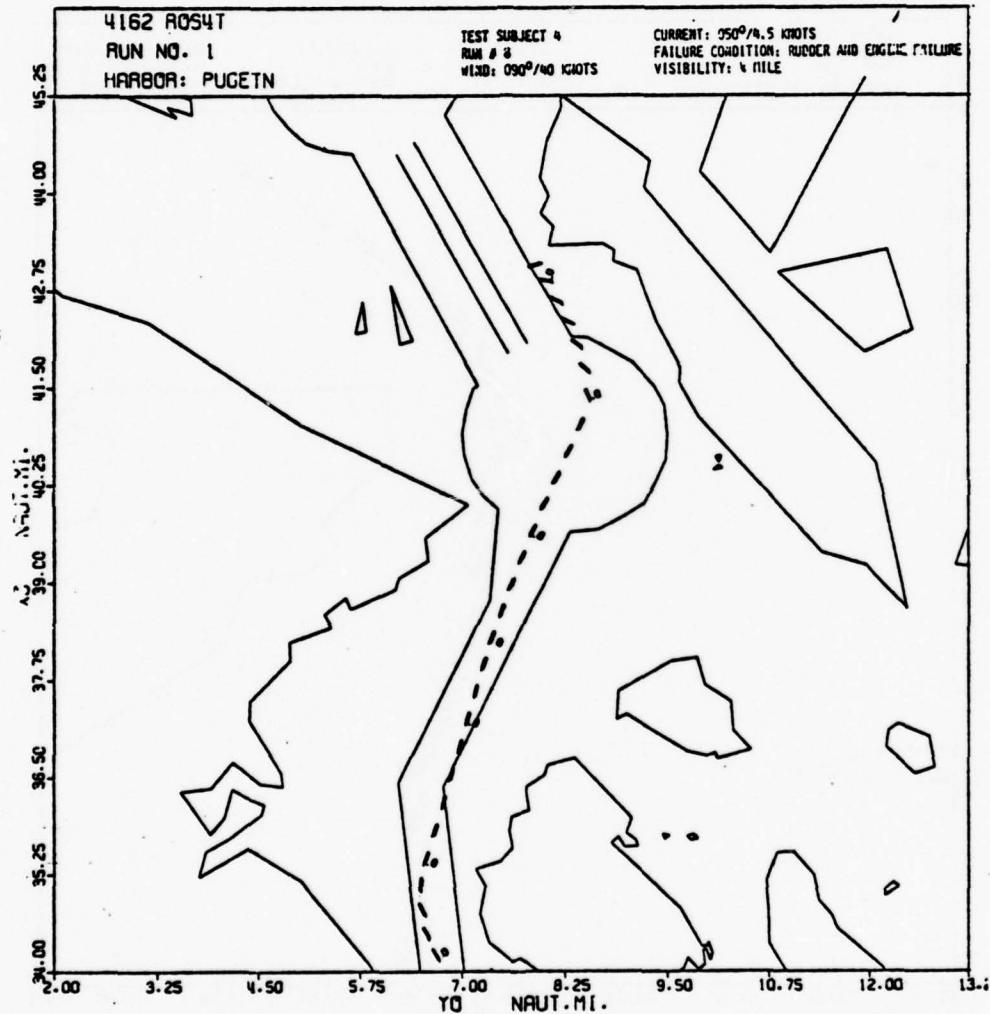












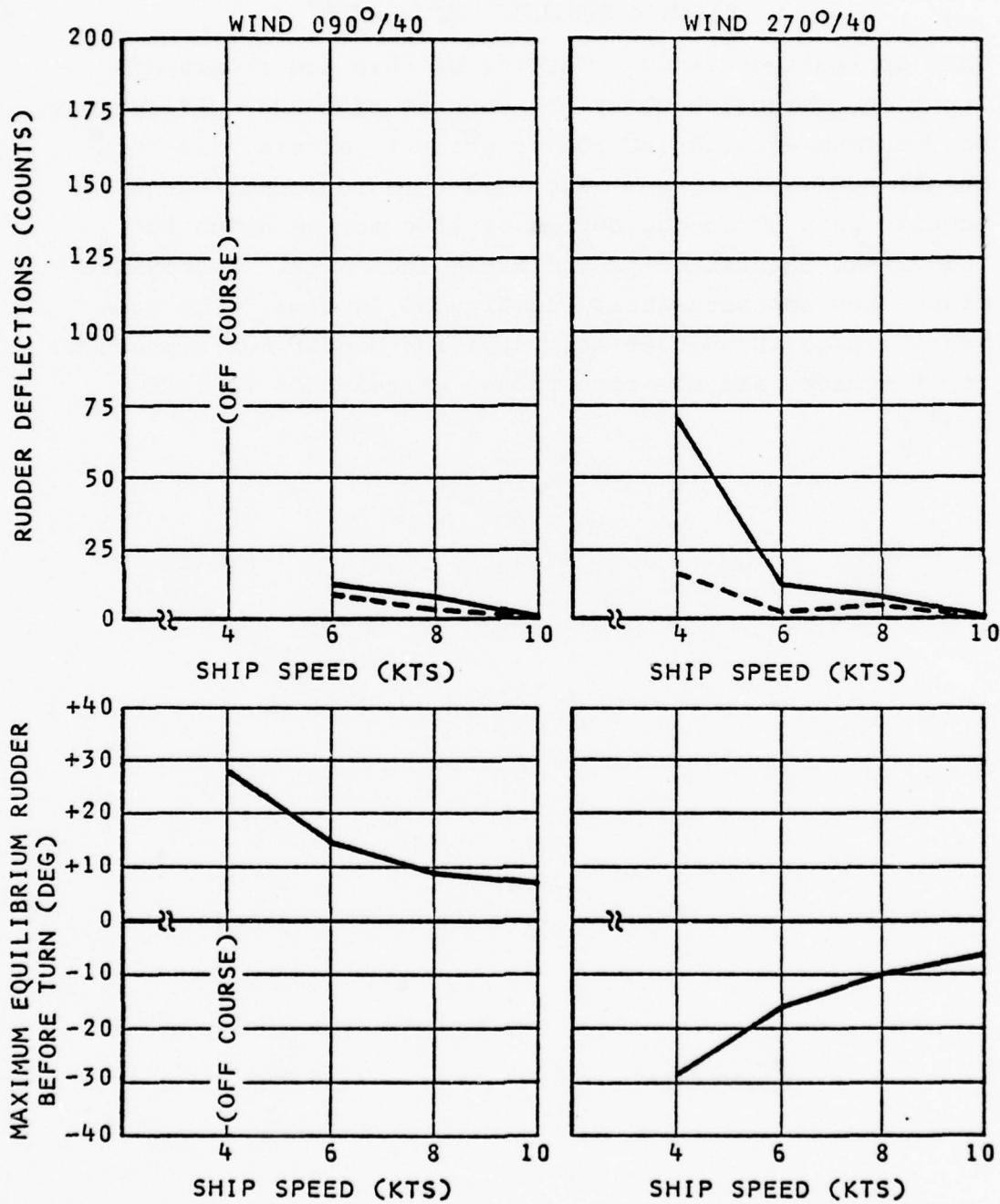
APPENDIX F

OFF-LINE TRACK KEEPING RUDDER DEFLECTION COUNTS AND MAXIMUM EQUILIBRIUM RUDDERS

This appendix contains a listing by ship and geographic location of the frequency (by counts) of rudder deflections, and maximum equilibrium rudder prior to a turn, all as a function of ship speed. The reader is reminded that a "count" is a 30 second period of time during which the rudder was maintained in the range indicated. Successive counts are not necessarily contiguous in time. The convention used throughout is: negative rudder corresponds to right rudder, and positive rudder corresponds to left rudder.

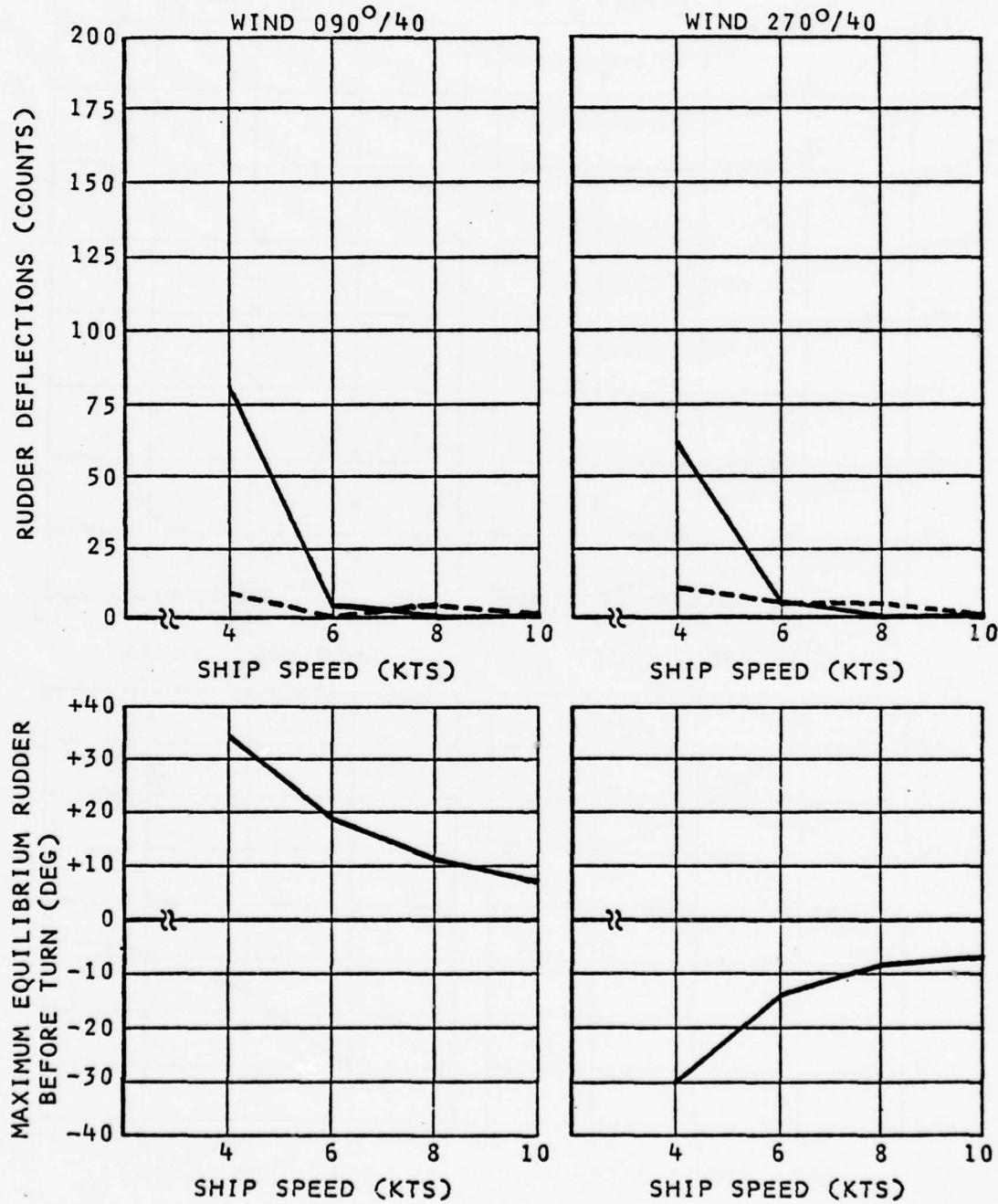
RUN DESCRIPTION:
SHIP 80,000 DWT
LOCATION ROSARIO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



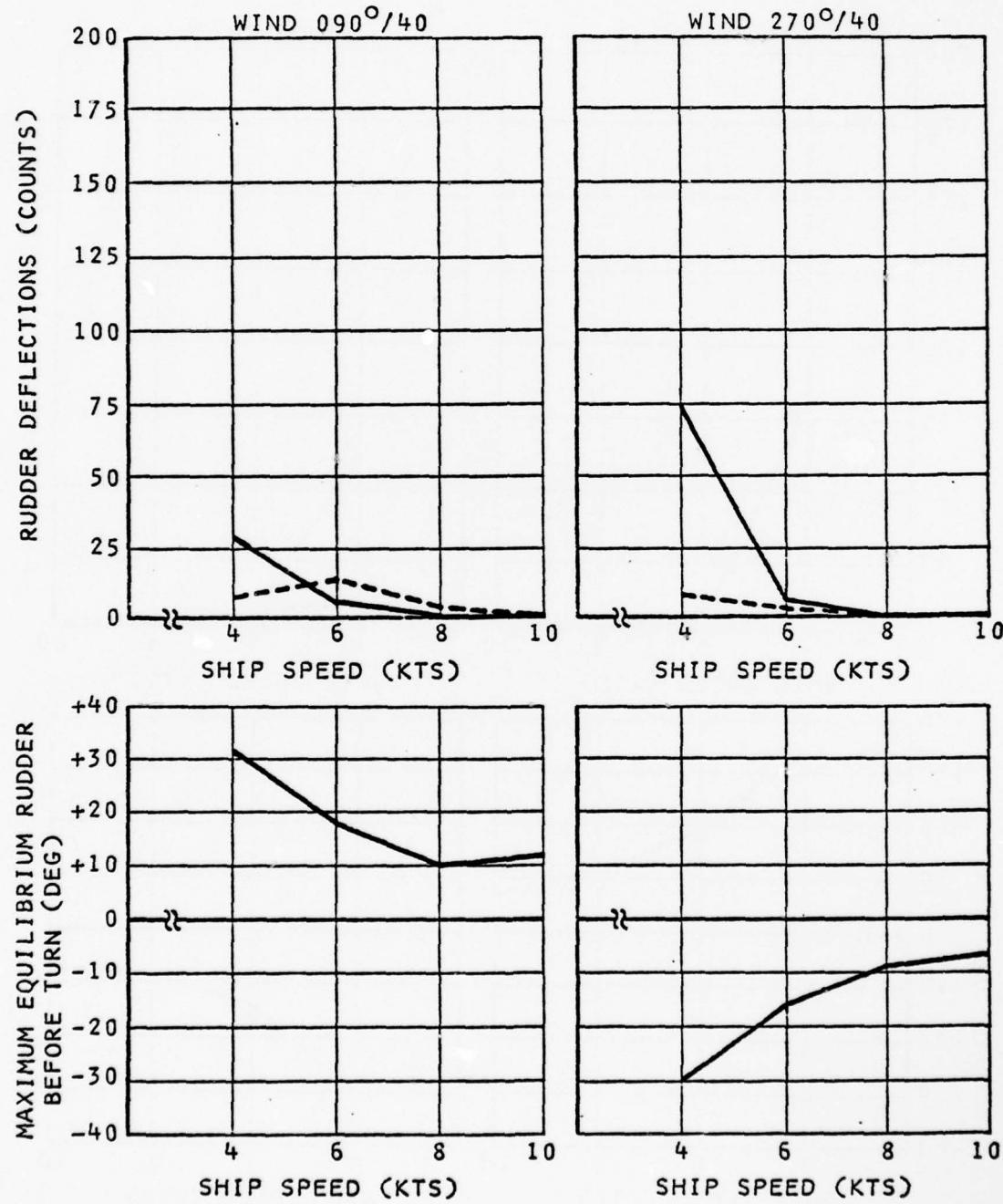
RUN DESCRIPTION:
SHIP 120,000 DWT
LOCATION ROSARIO STRAIT

RUDDER ANGLES
--- 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



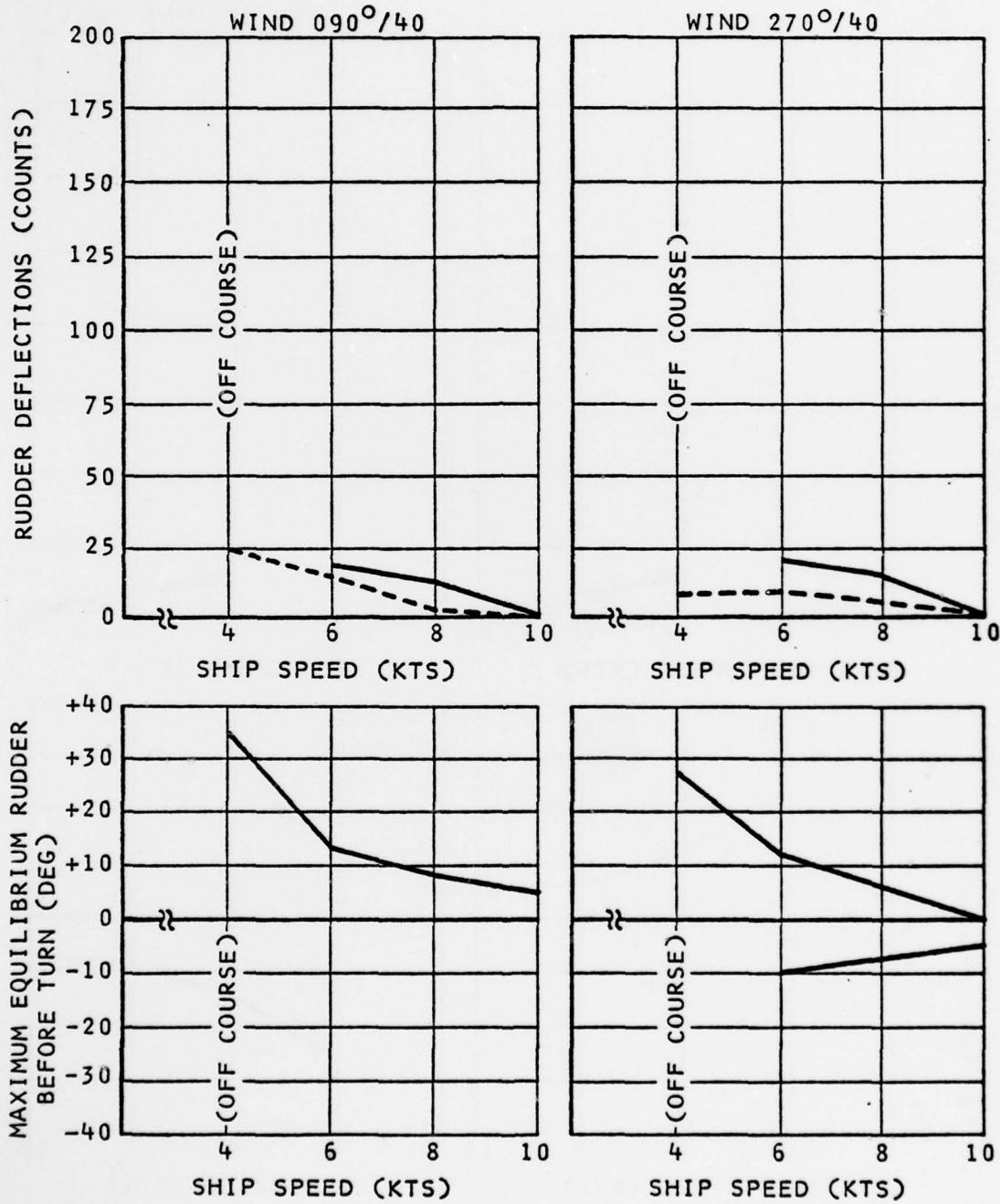
RUN DESCRIPTION:
SHIP 165,000 DWT
LOCATION ROSARIO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



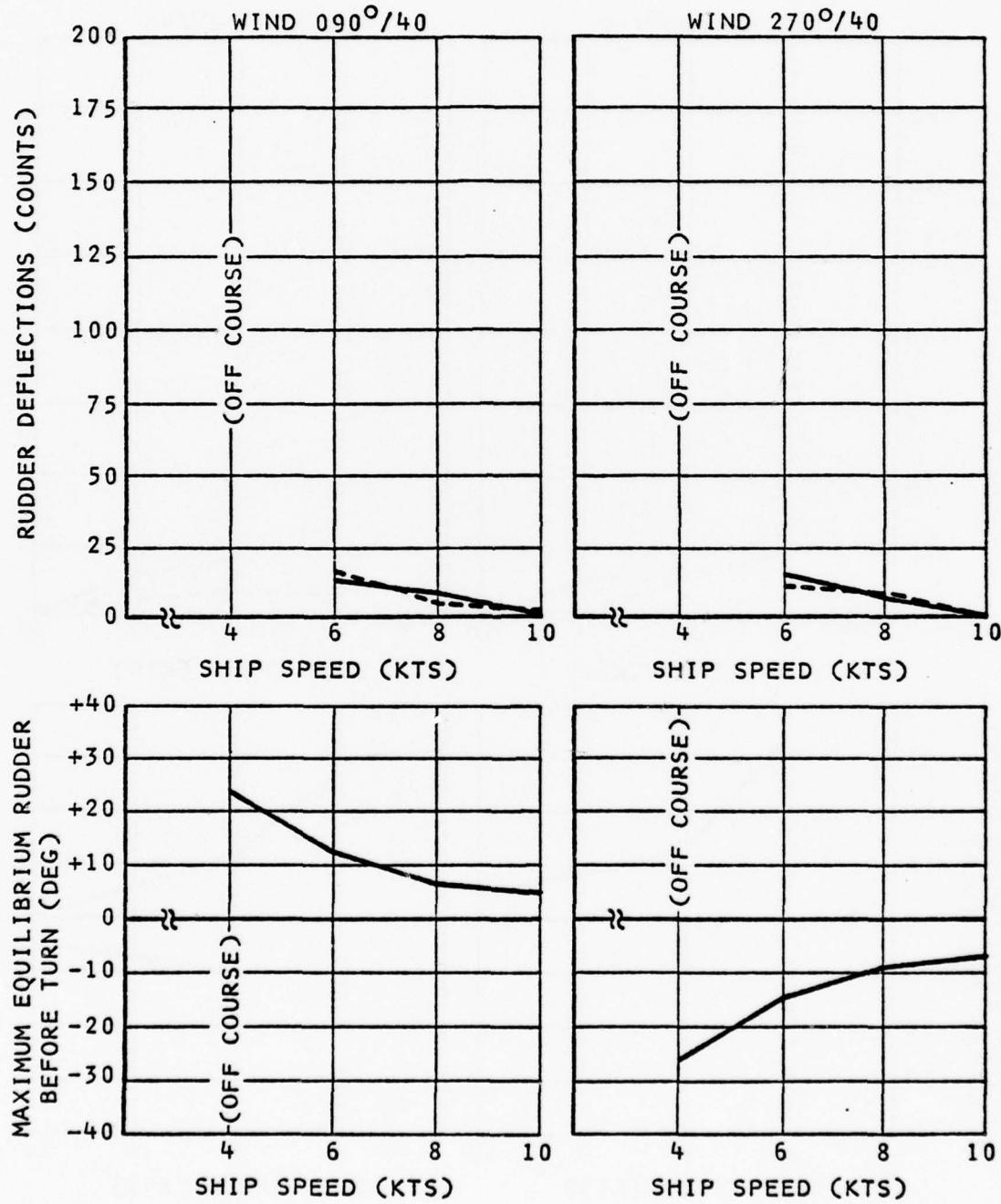
RUN DESCRIPTION:
SHIP 280,000 DWT
LOCATION ROSARIO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



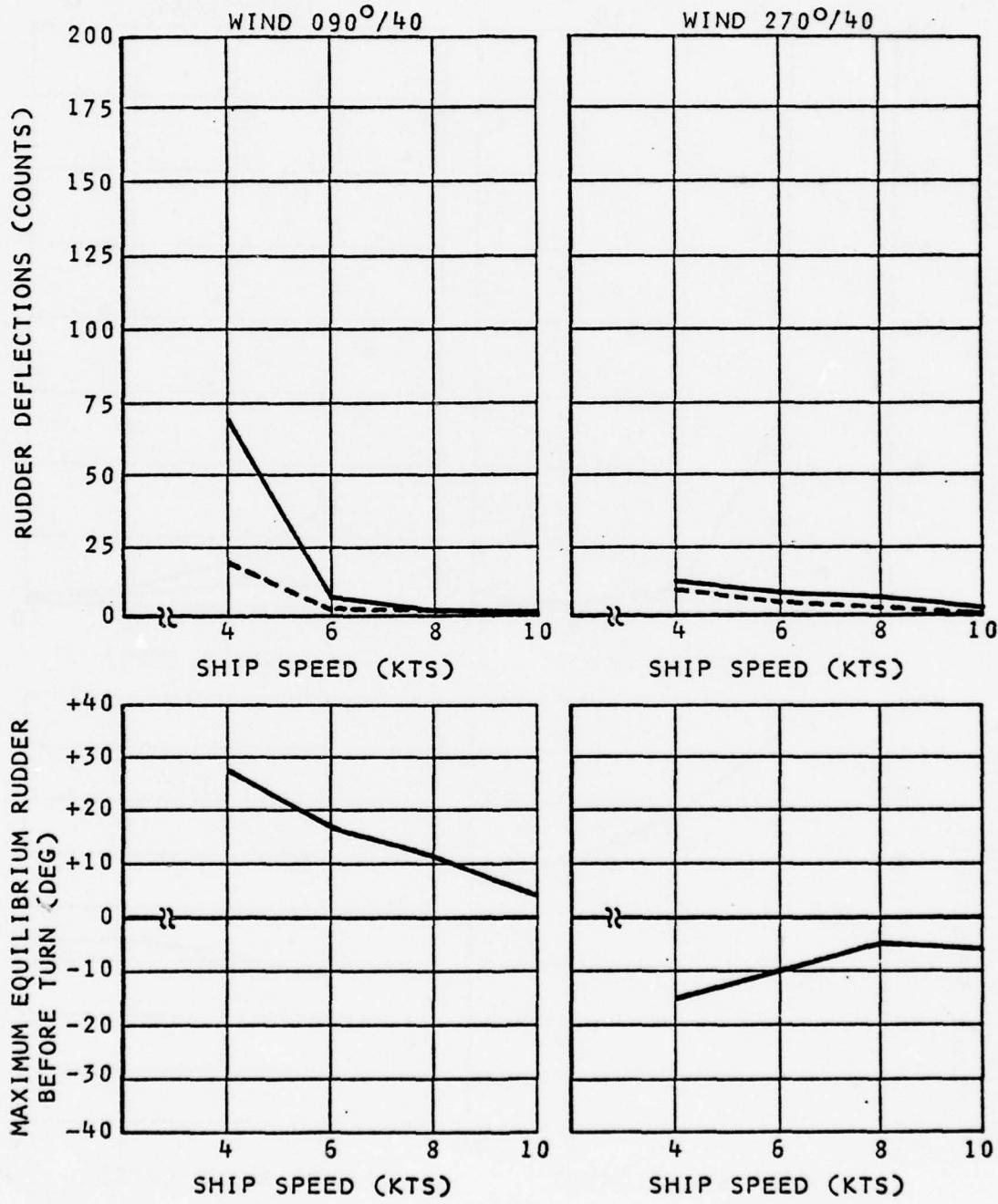
RUN DESCRIPTION:
SHIP 400,000 DWT
LOCATION ROSARIO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



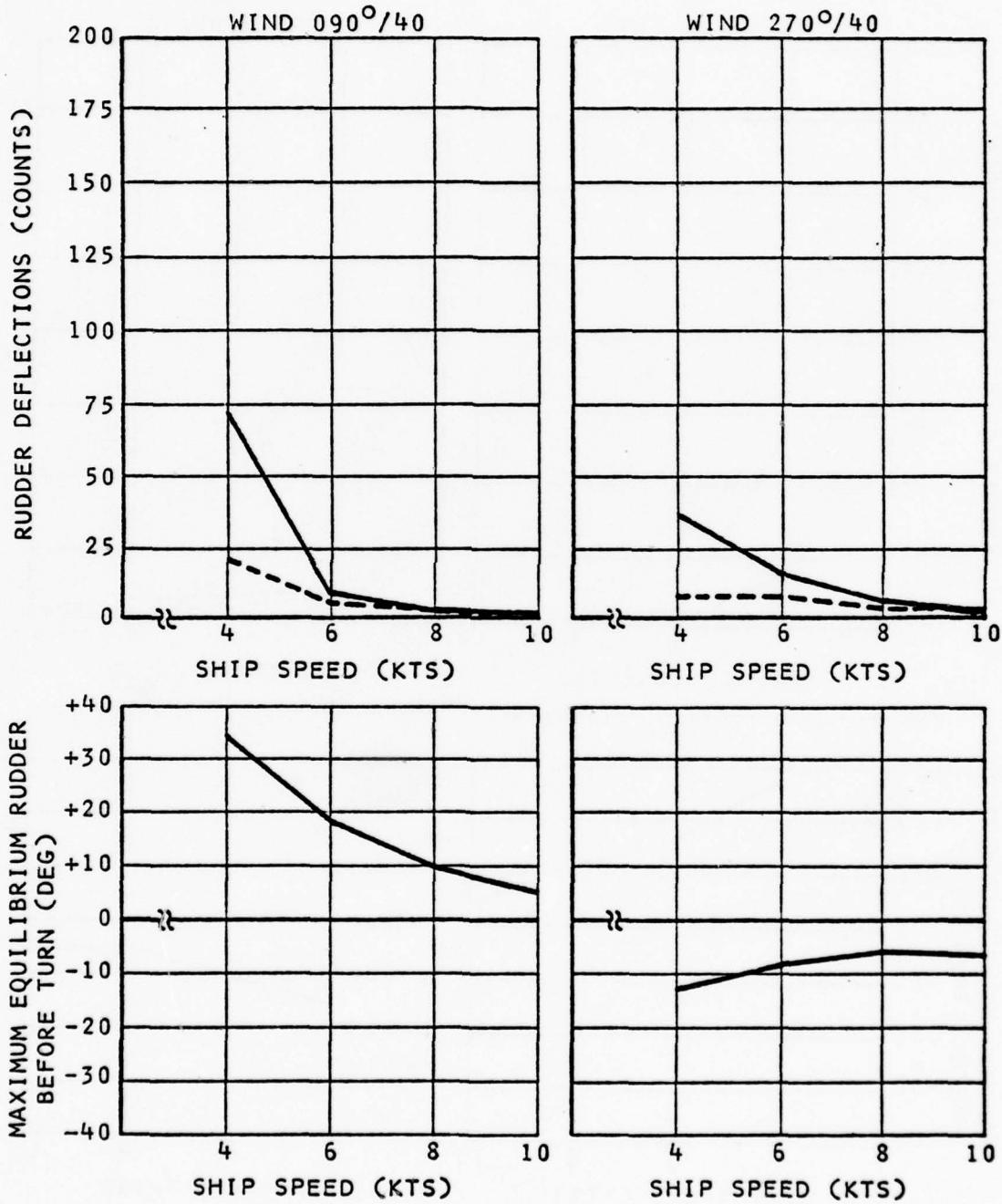
RUN DESCRIPTION:
SHIP 120,000 DWT
LOCATION HARO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



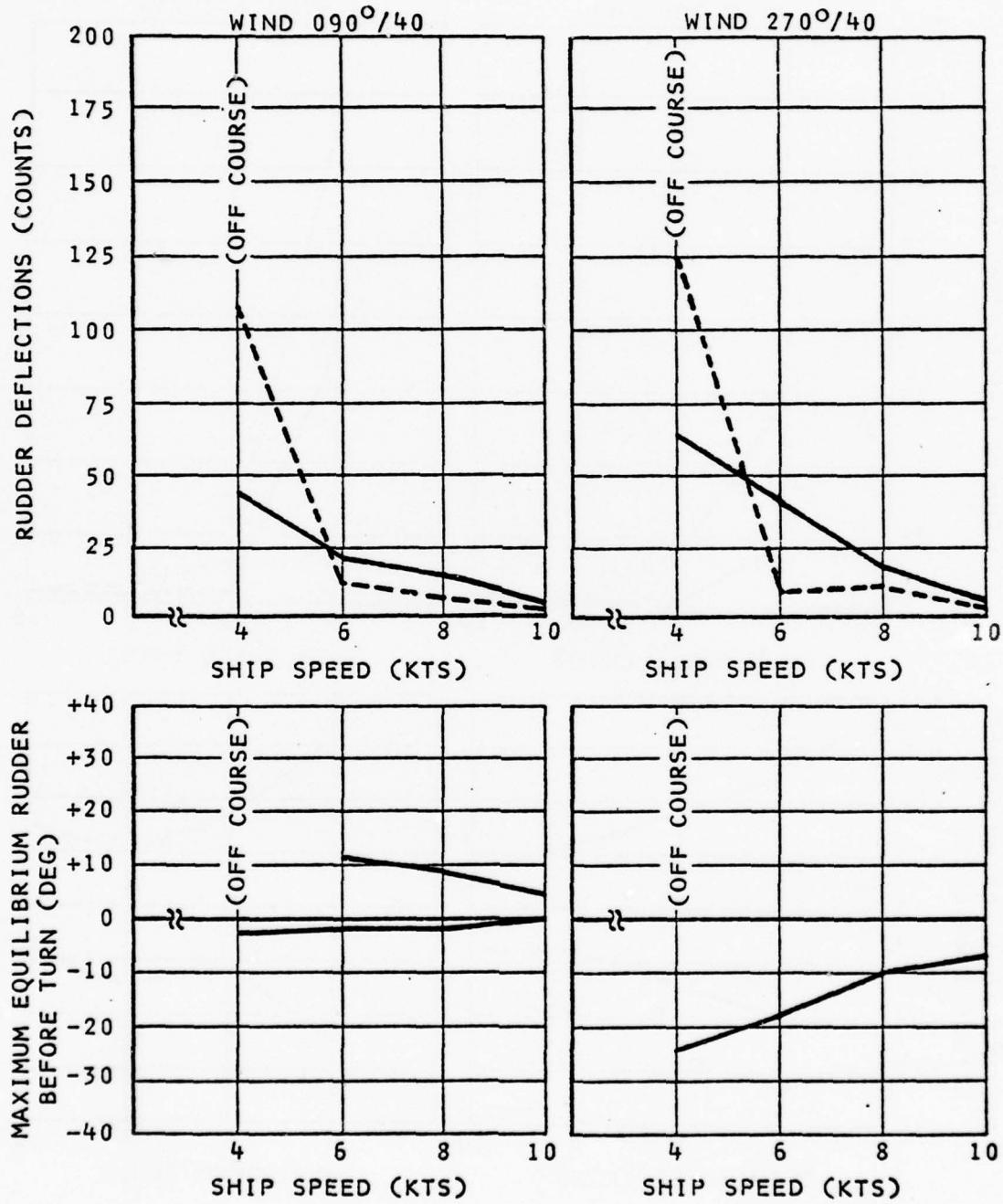
RUN DESCRIPTION:
SHIP 165,000 DWT
LOCATION HARO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



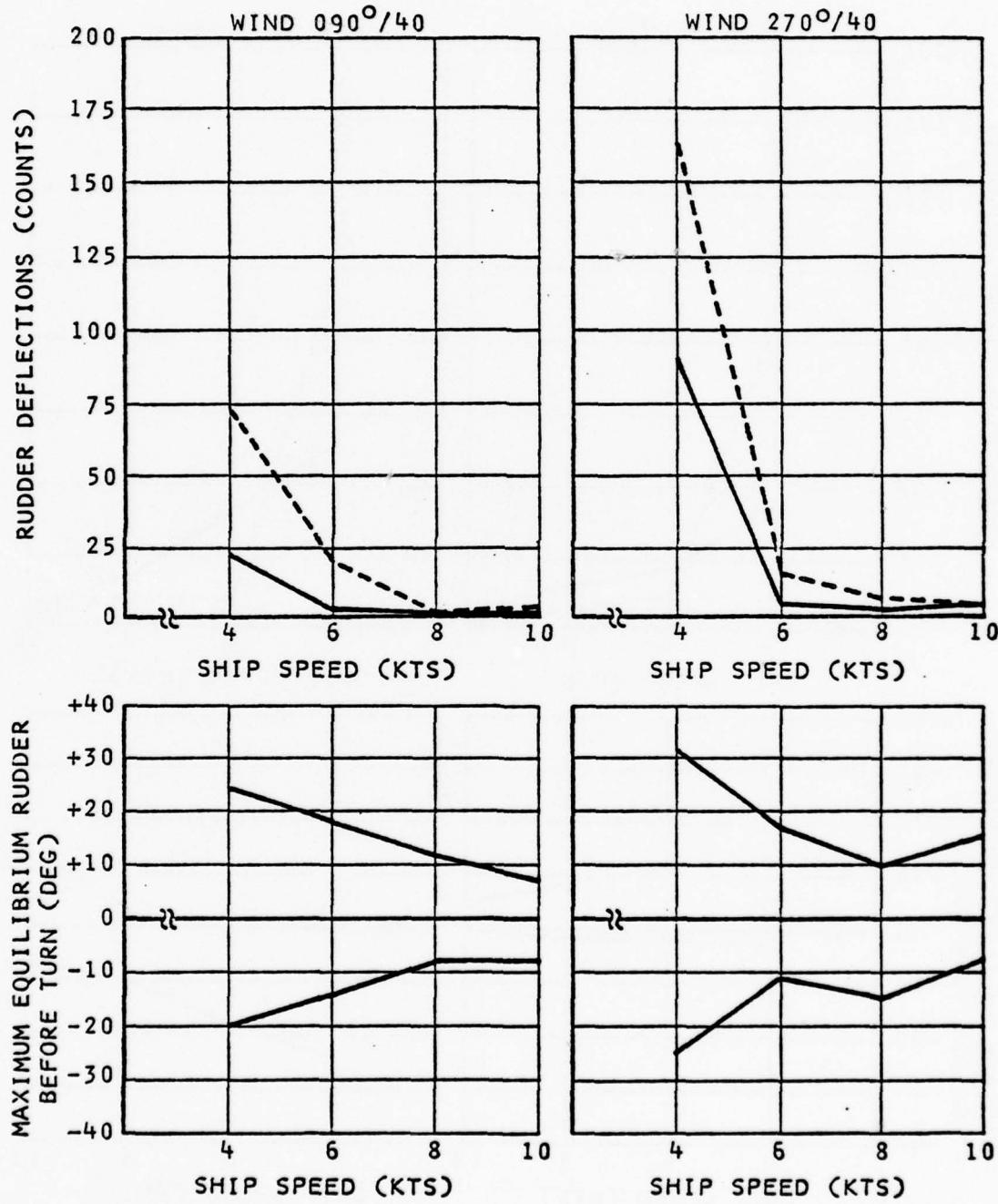
RUN DESCRIPTION:
SHIP 400,000 DWT
LOCATION HARO STRAIT

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



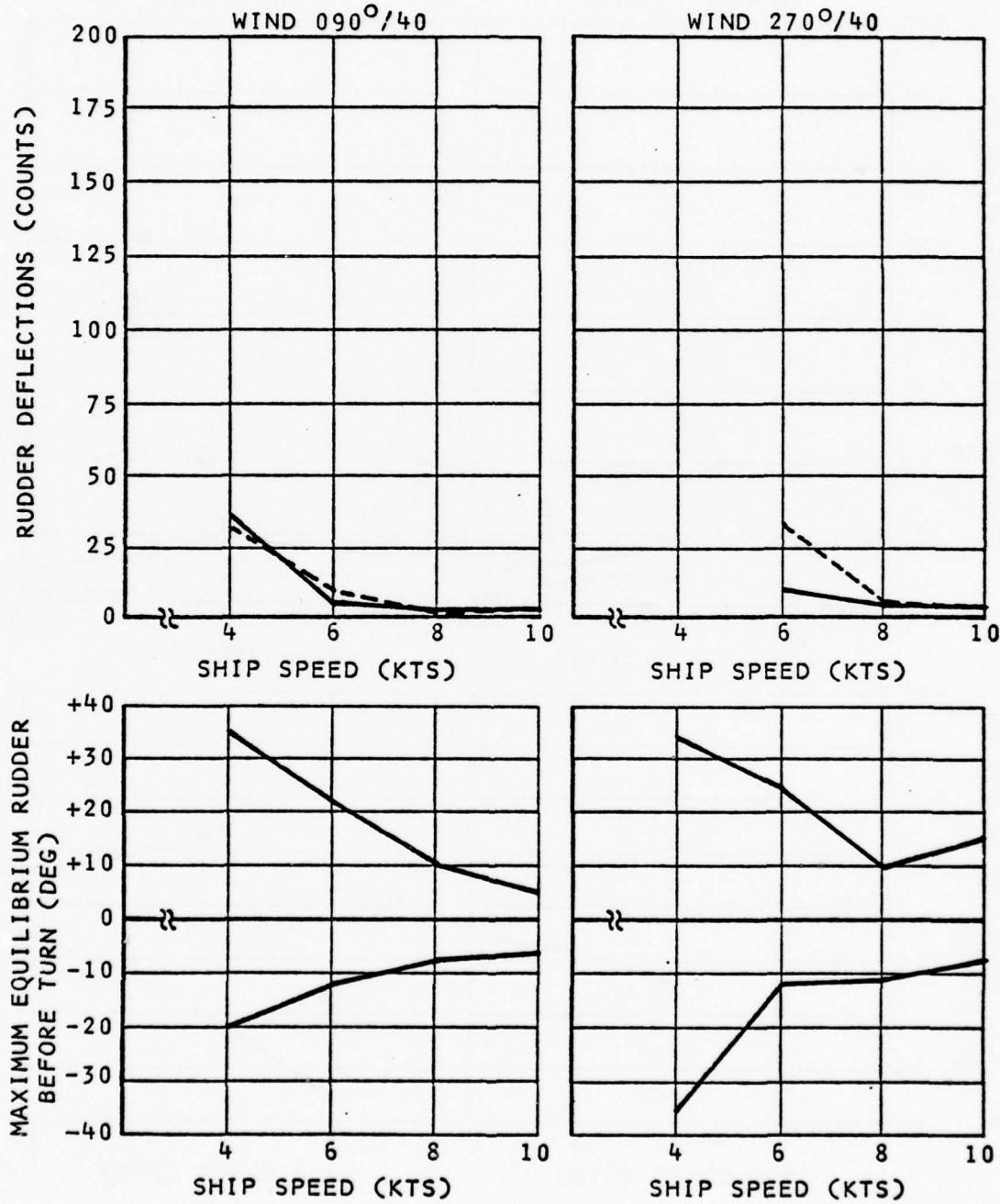
RUN DESCRIPTION:
SHIP 120,000 DWT
LOCATION BELLINGHAM CHANNEL.

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



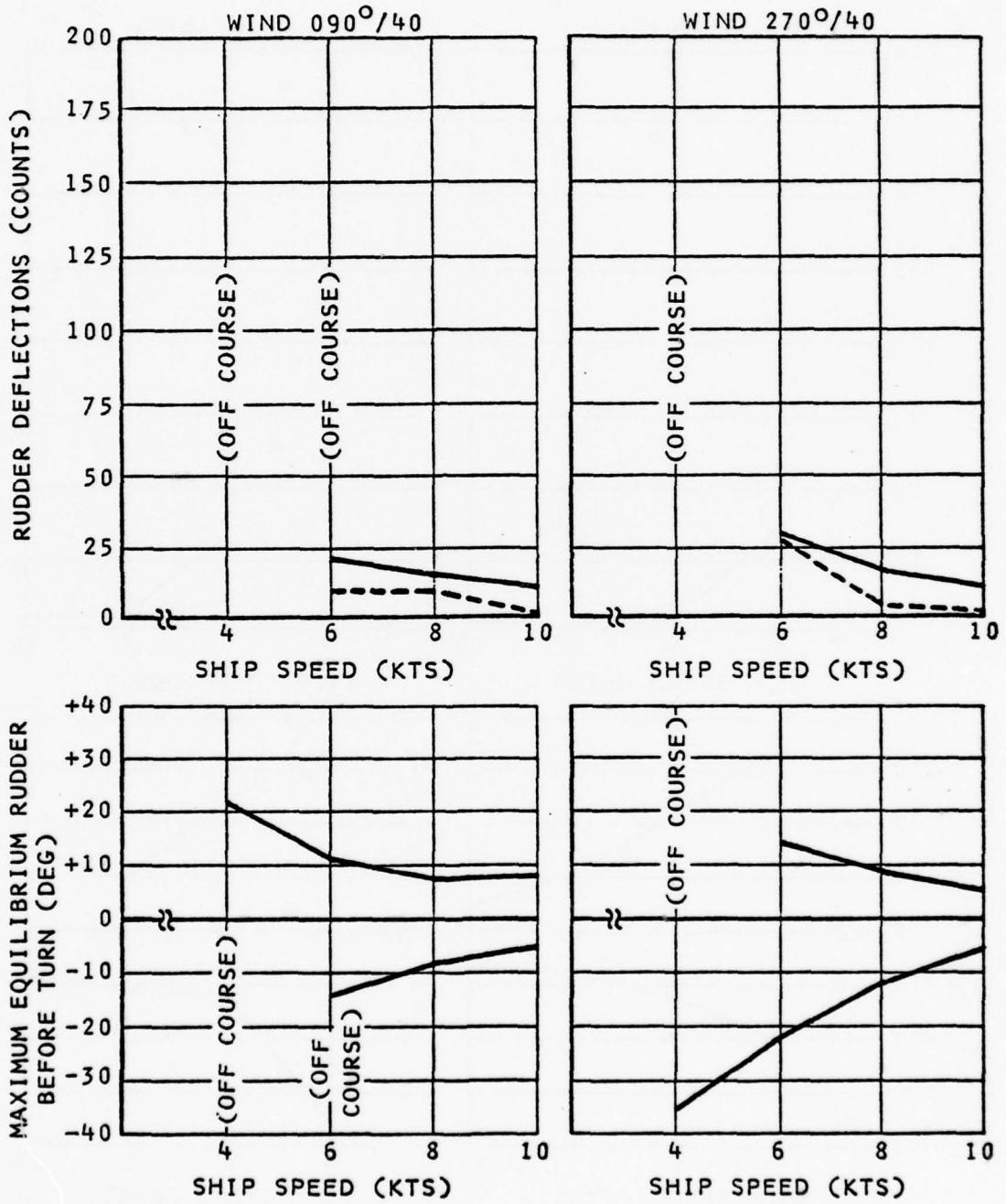
RUN DESCRIPTION:
SHIP 165,000 DWT
LOCATION BELLINGHAM CHANNEL

RUDDER ANGLES
- - - 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



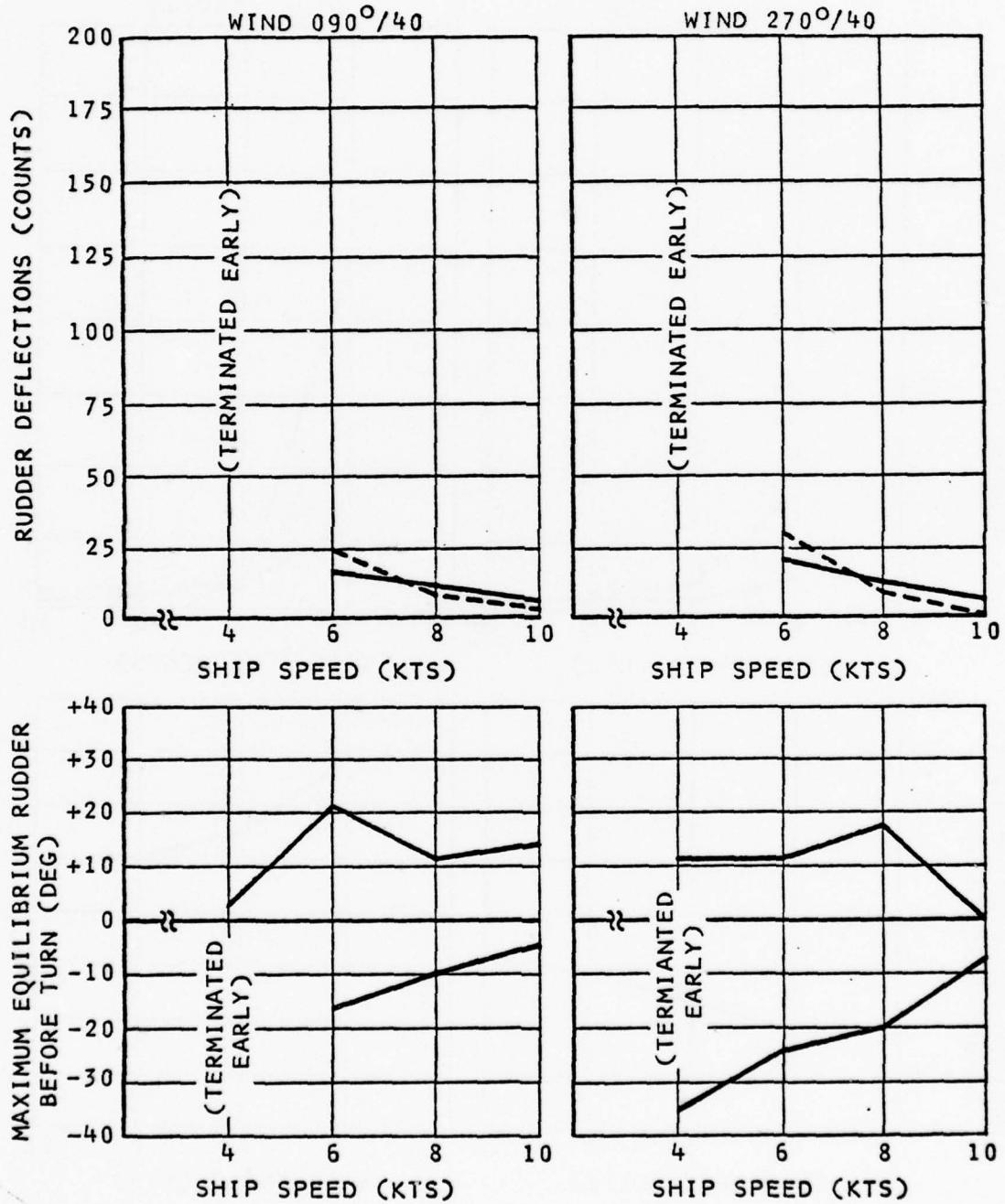
RUN DESCRIPTION:
SHIP 280,000 DWT
LOCATION BELLINGHAM CHANNEL

RUDDER ANGLES
--- 20° TO $27\frac{1}{2}^{\circ}$
— $27\frac{1}{2}^{\circ}$ TO 35°



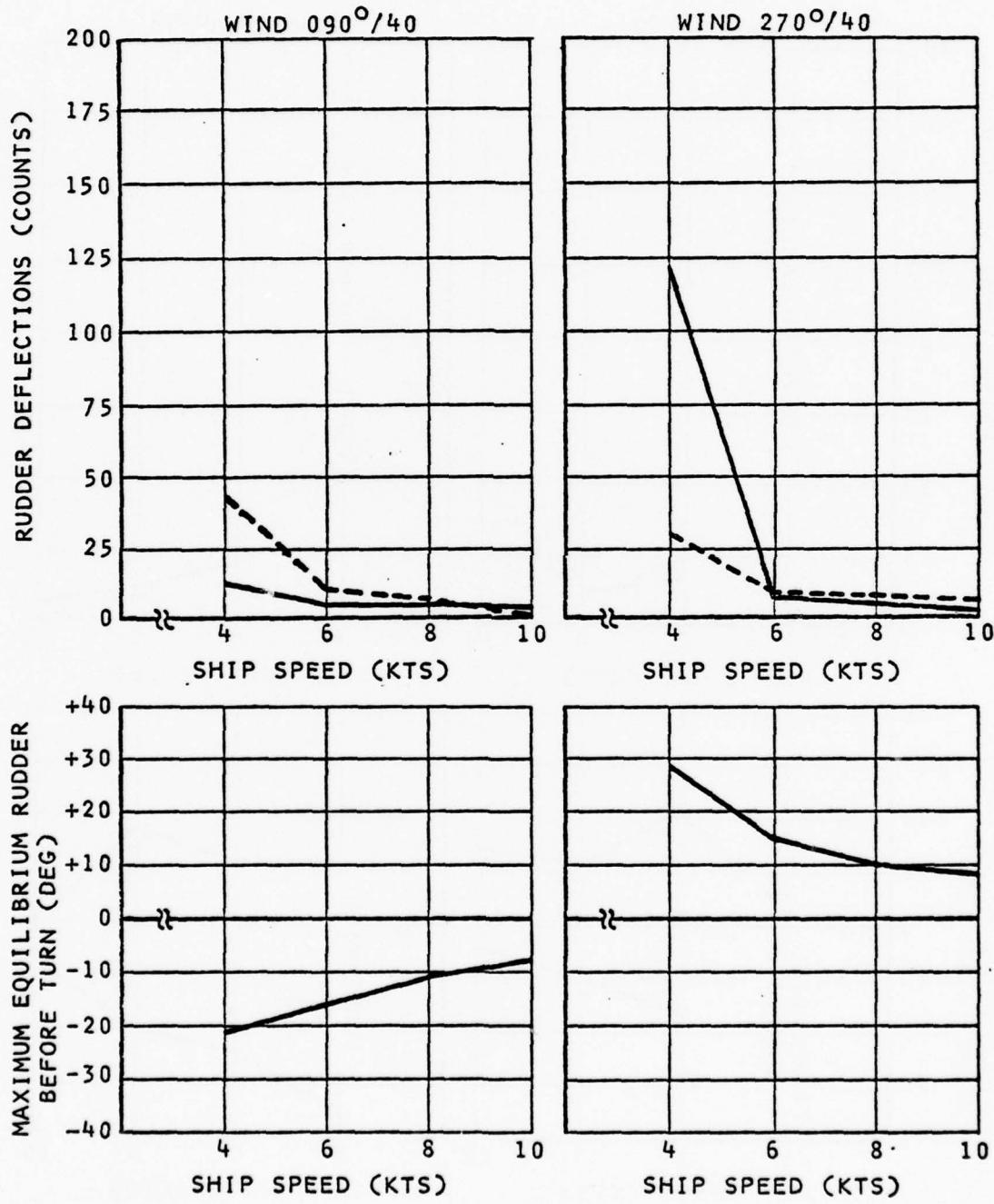
RUN DESCRIPTION:
 SHIP 400,000 DWT
 LOCATION BELLINGHAM CHANNEL

RUDDER ANGLES
 - - - 20° TO $27\frac{1}{2}^\circ$
 - - - $27\frac{1}{2}^\circ$ TO 35°



RUN DESCRIPTION:
SHIP 120,000 DWT
LOCATION ADMIRALTY INLET

RUDDER ANGLES
--- 20° TO $27\frac{1}{2}^\circ$
— $27\frac{1}{2}^\circ$ TO 35°



APPENDIX G

PLOTS OF OFF-LINE TRACK KEEPING RUNS

This appendix contains the plots of all ground tracks made by ships off-line under the control of an autopilot.



T BODYTYPE

ROARIO

U CT U WIND DIR U CRNT DIR

14.0 40.0 270.0 4.8 200.0

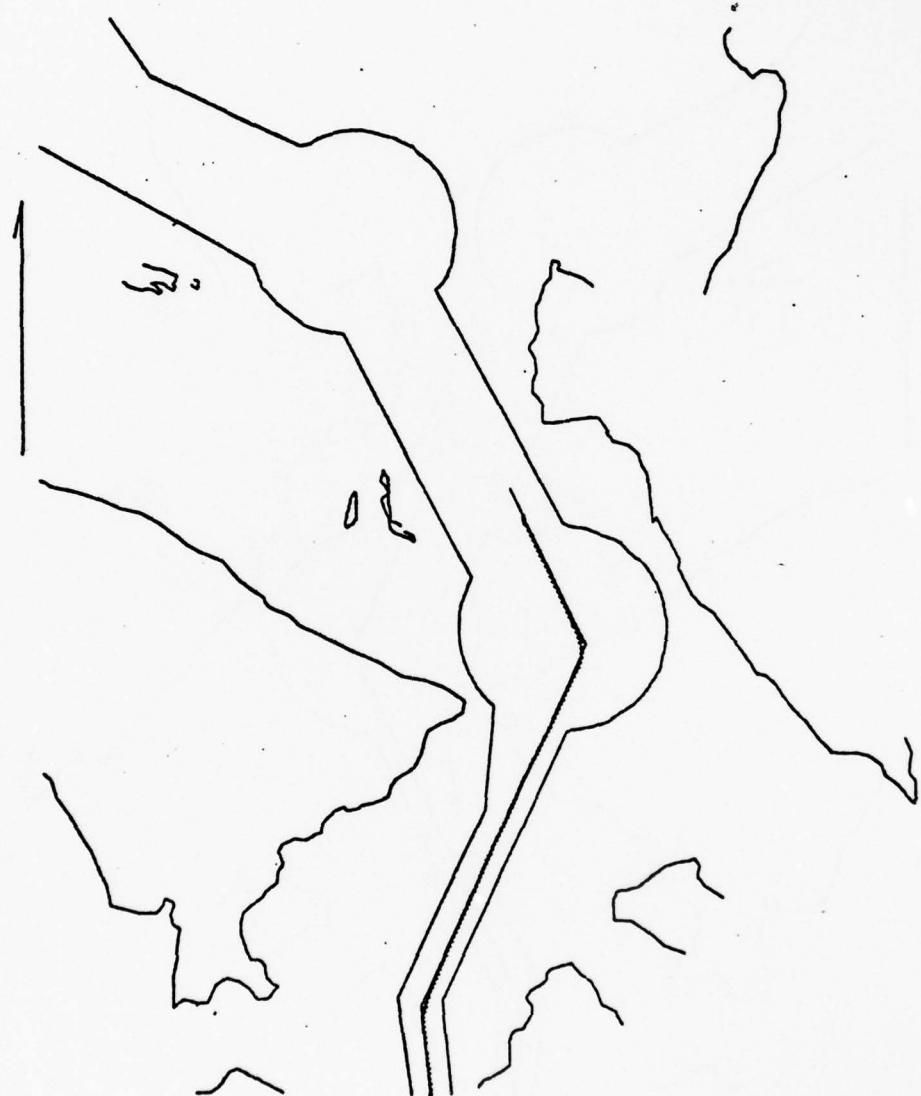


T 100 TYPE

POGARIO

U CT U WIND DTR U CRNF DTR

14.0 40.0 90.0 4.5 200.0



T BOTTOM

RORARIO

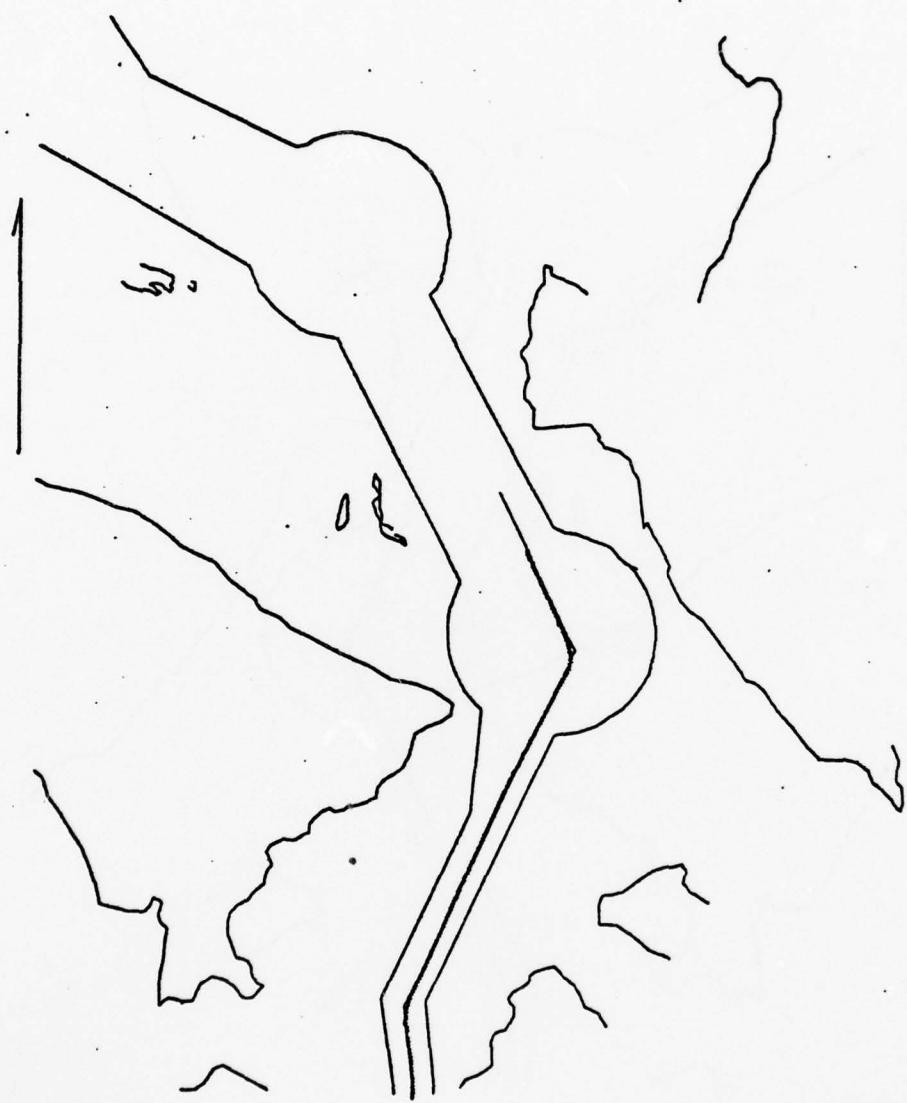
U ET U WIND DIR U CNT DIP

12.8 48.8 270.0 4.8 200.6

G-4



T 807, PC
PO'ARIO
U CT U WIND DIR. U CRNT DIR.
12.0 48.0 93.0 1.8 200.0



T 60 TYPE

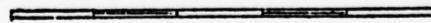
ROPARIO

U ET U WIND DIR U CNT DIR

10.0 40.0 270.0 4.8 200.0



1 BOTYPE
ROARARIO
U ET U WIND DIR U LONG DIR
10.0 40.0 90.0 1.0 200.0



T BOTTLE

ROARIO

U ET U WIND DIR U GANT DIR

8.0 48.0 270.0 2.8 21.0



—

F BOTYPE

ROARIO

U ET U WIND DIR U CNT DIR

8.0 48.0 90.0 3.0 20.0



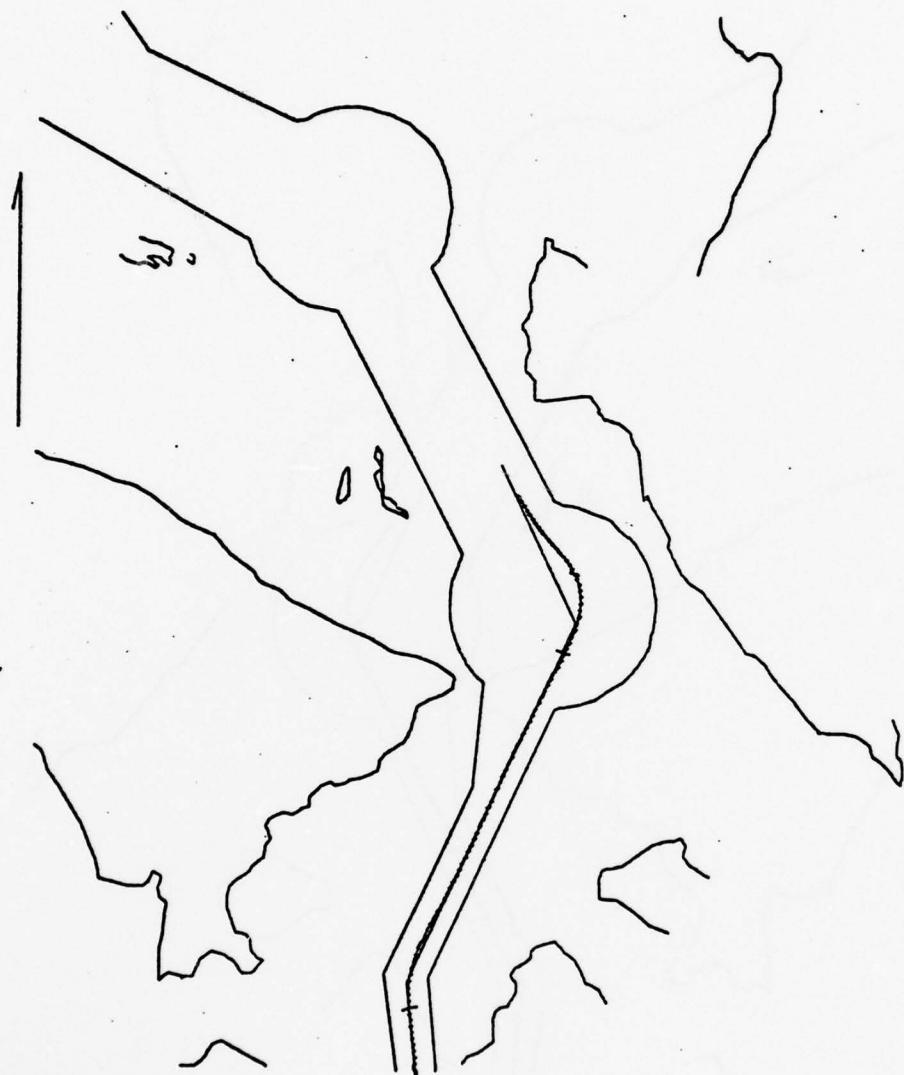
—

T BOTTLE

POBARIO

U CT' U WIND DIR. U CNT' DIR.

6.0 40.0 276.0 3.8 26.0



T DOTYPE

ROAPIO

U E1 U WIND DIP. U CONY DIP

6.0 40.0 90.0 3.0 20.0

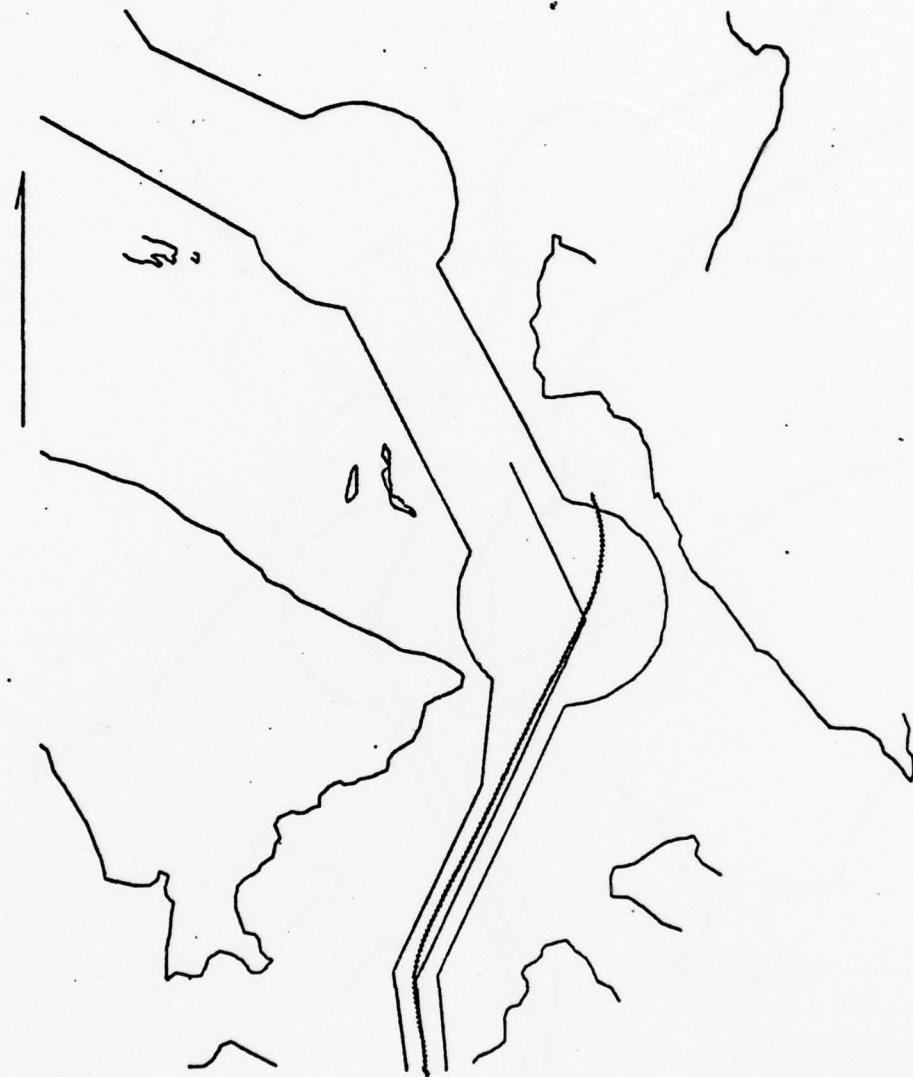


T ROTYPE

ROBARIO

U ET U WIND DIR U CRNT DIR
4.0 48.0 270.0 2.8 28.0

G-12



T BTYPE

ROSARIO

U ET U WIND DIR U CRNT DIR

4.0 40.0 90.0 3.6 20.0

G-13



T 208 TYPE

ROSARIU

U-CT U WIND DIR U CNT DIR

10.0 40.0 270.0 4.0 200.0



T 290T/PC

POSARIO

U ET U WIND DIR U CNT TIR

10.0 40.0 90.0 4.8 200.0



T 200 TYPE

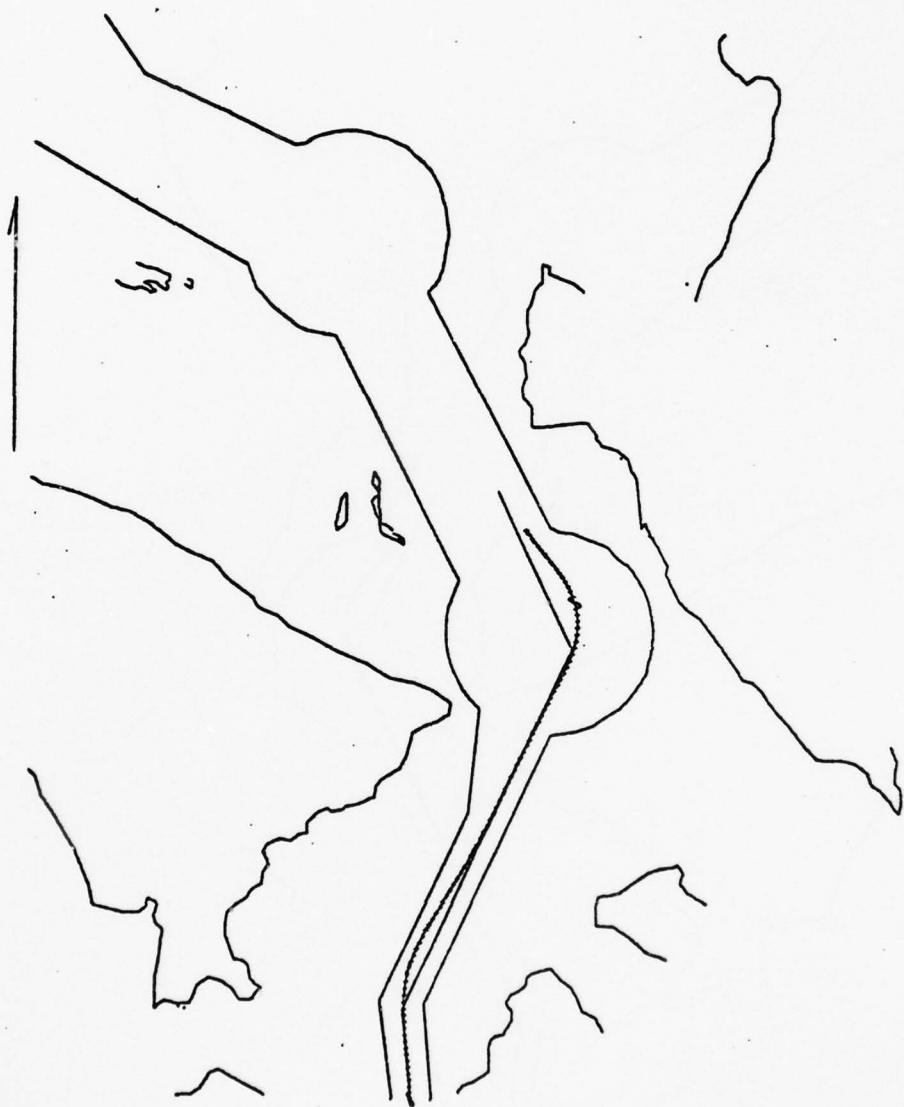
POARIO

U ET U WIND DIR U CRNT DIR

8.8 46.0 270.0 3.8 26.0



T 298TYPE
ROARIO
U ET U WIND DIR U CNT DIR
8.0 40.0 90.0 2.0 20.0



T 238TYPE

ROCARIO

U ET U WIND DIR U CNT DIR

6.0 40.0 270.0 3.8 28.0

AD-A062 085

NATIONAL MARITIME RESEARCH CENTER KINGS POINT NY

F/G 13/10

AN INVESTIGATION INTO SAFETY OF PASSAGE OF LARGE TANKERS IN THE--ETC(U)
OCT 78 J RIEK, S TENENBAUM, W MCILROY

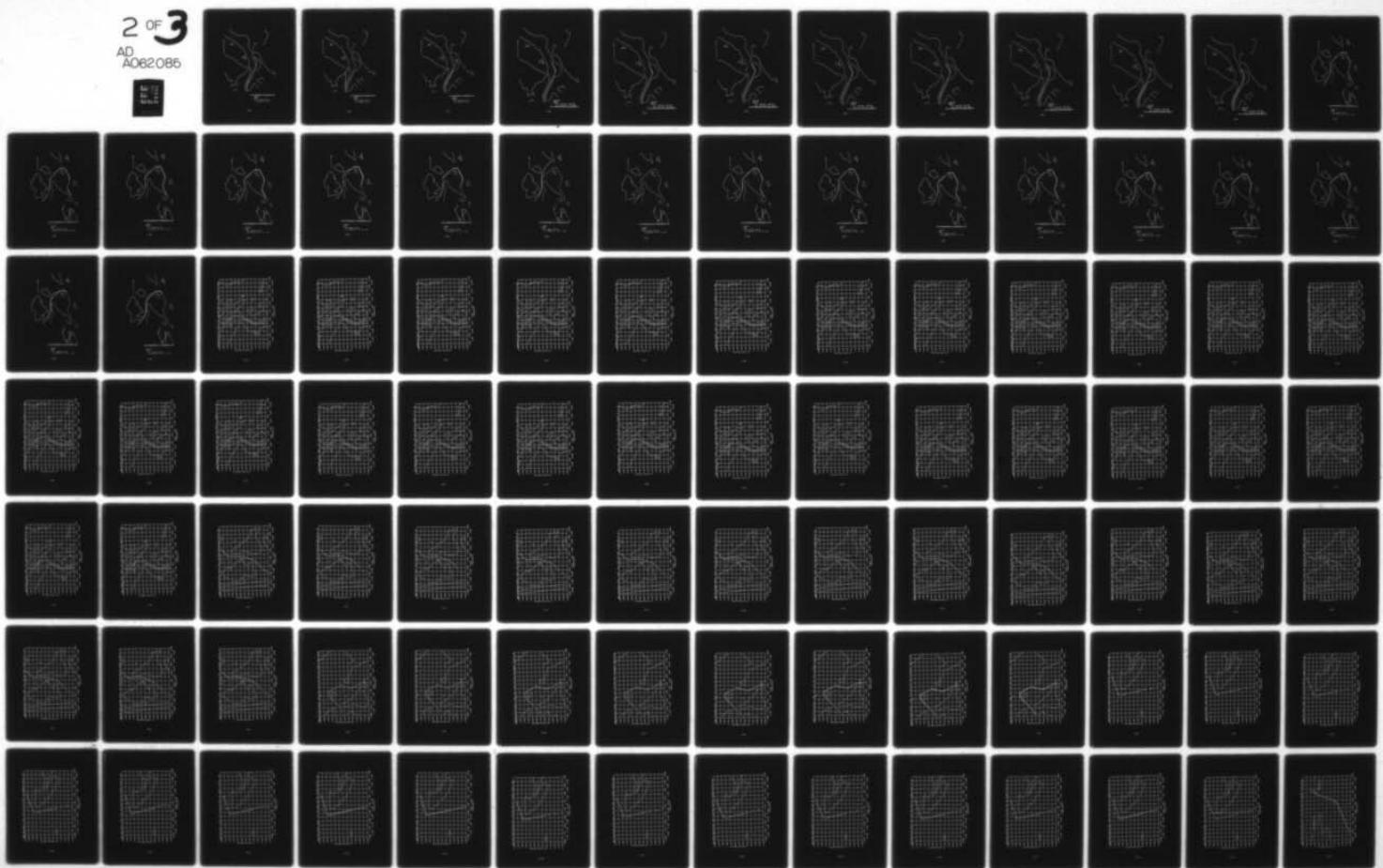
MIPR-Z70099-8-843822

USCG-D-79-78-APP-2

NL

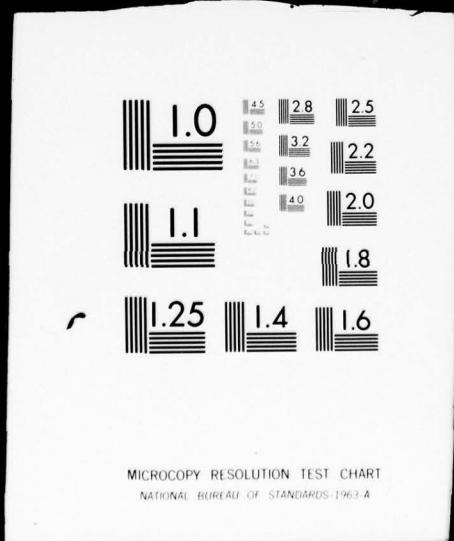
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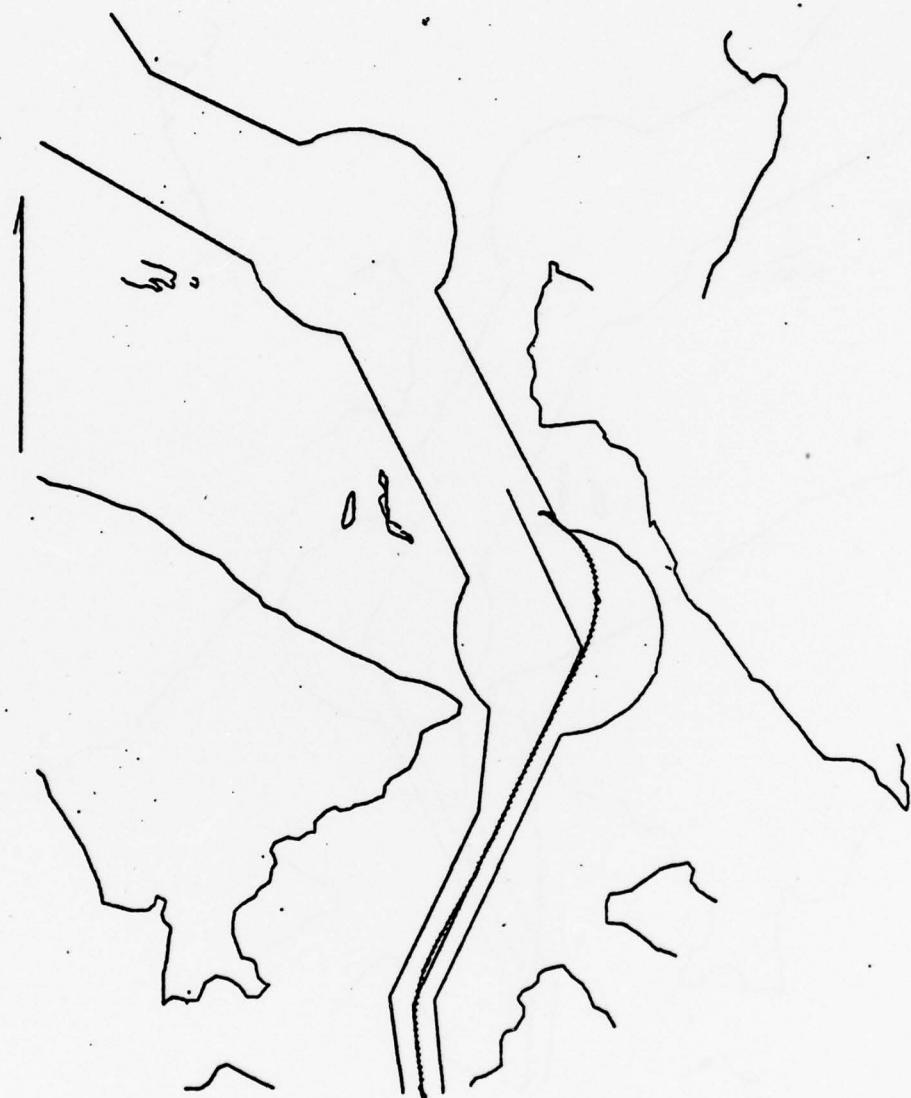
2 OF 3
AD
A062085



2 OF 3

AD
A062085





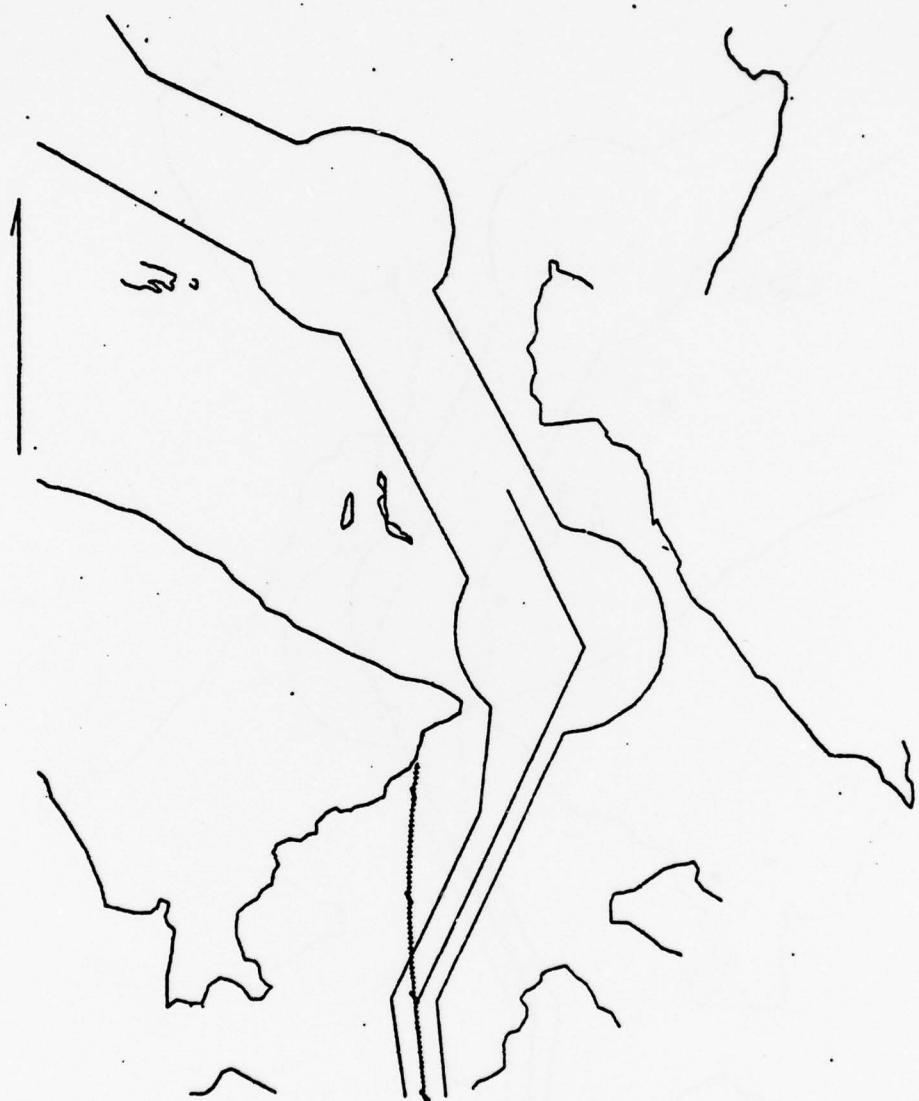
F 200 TYPE

ROBARTO

U ET U WIND DIR U CNT DIR

6.0 40.0 90.0 2.0 20.0

G-19

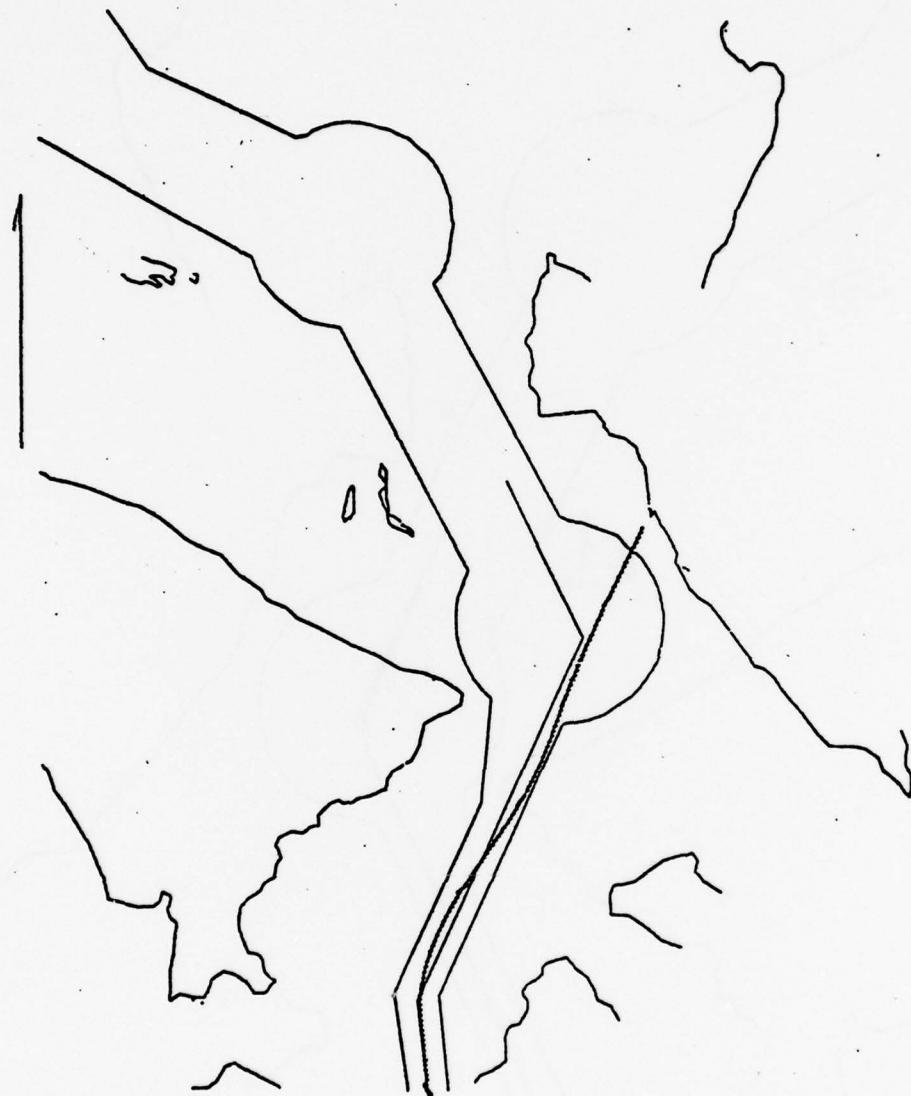


F 290 TYPE

ROSARIO

U ET U WIND DIR U CANT DIR

4.0 46.0 270.0 3.0 20.0

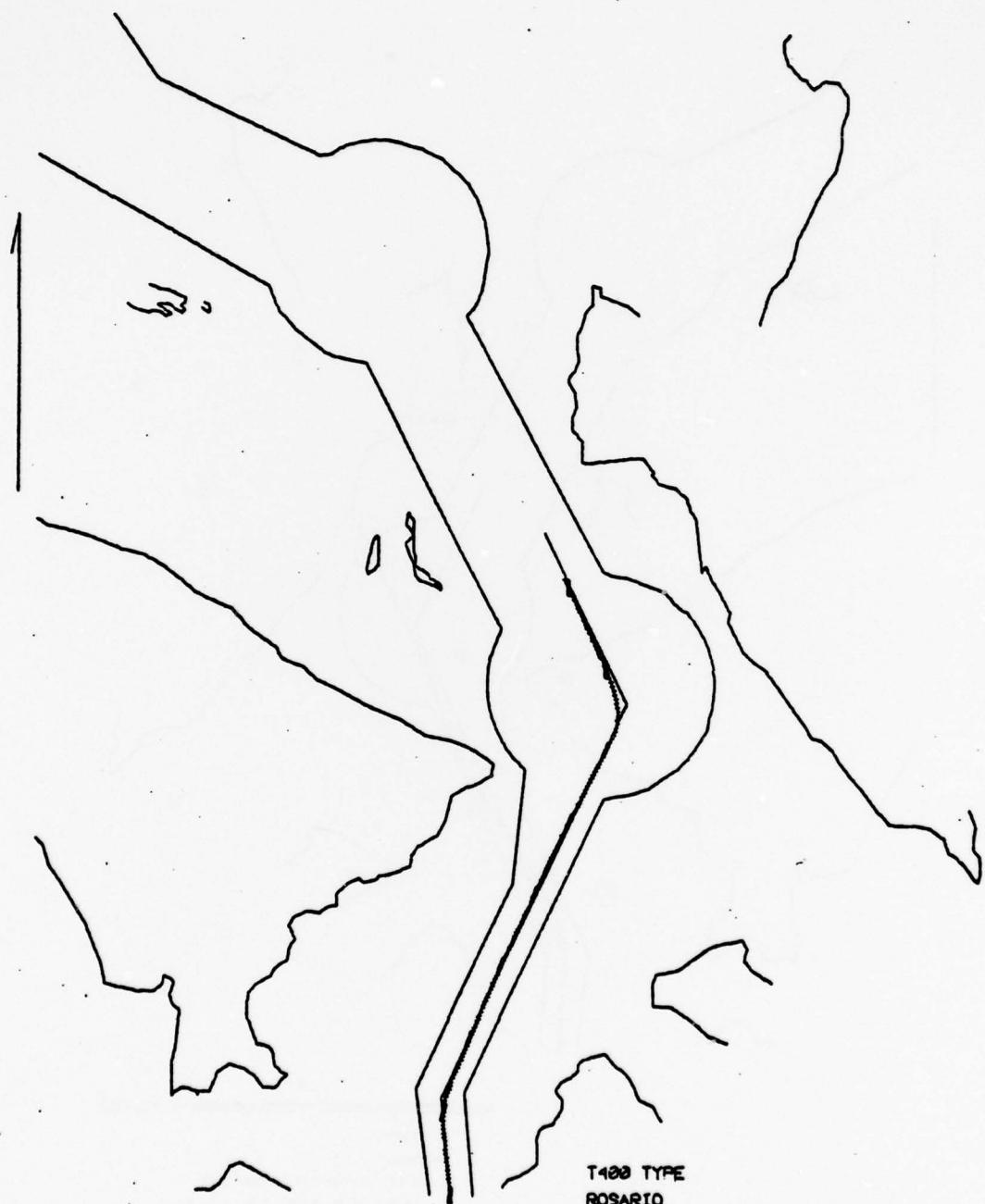


I 280 TYPE

PORARIO

U ET U WIND DIR U CANT DIR

4.0 48.0 90.0 2.8 20.0



T400 TYPE
ROSARIO

U KT U WIND DIR U CRNT DIR
10.0 10.0 270.0 4.8 200.0



T400 TYPE
ROSARIO

| U KT | U WIND DIR | U CRNT DIR |
|------|------------|------------|
| 10.0 | 40.0 | 90.0 |
| 4.8 | 200.0 | |

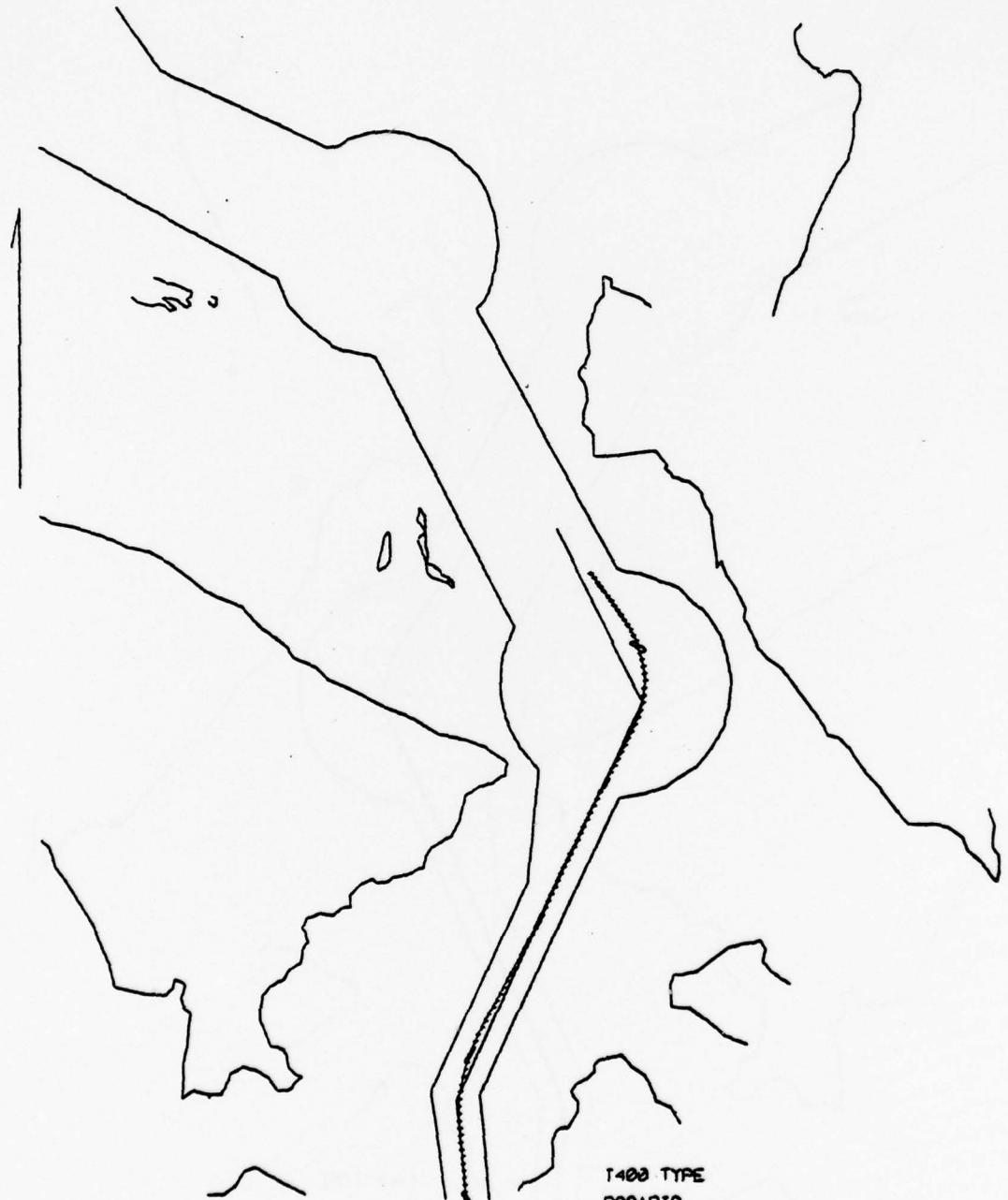


G-24



T400 TYPE
ROSARIO

U KT U WIND DIR. U CRNT DIR
8.0 40.0 90.0 3.8 20.0



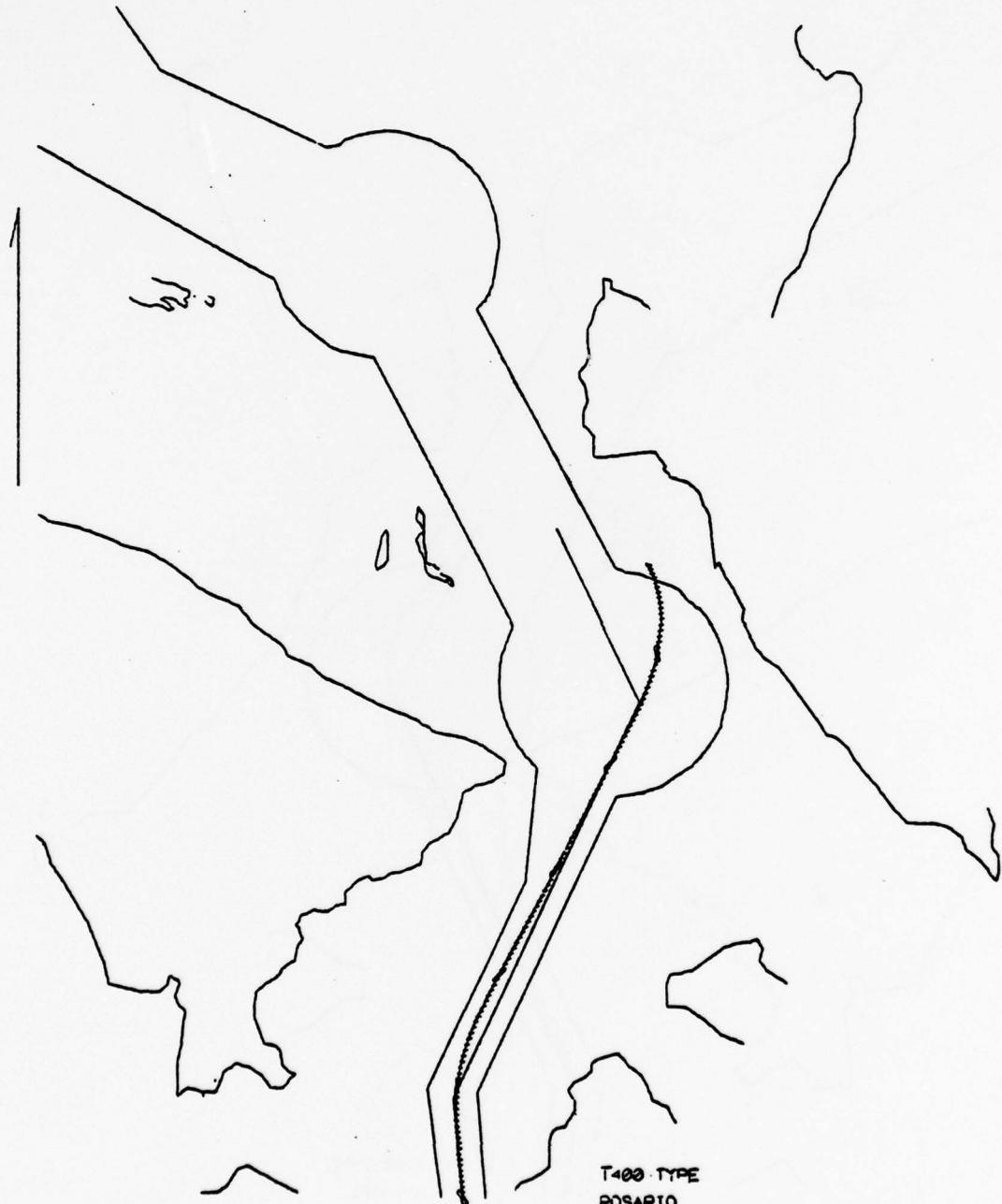
T400 TYPE
ROSARIO

U KT U WIND DIR U CRNT DIR
6.0 40.0 270.0 3.8 20.0



T400 TYPE
ROSARIO

U KF U WIND DIR U CRNT DIR
6.0 40.0 90.0 3.8 20.0



G-28



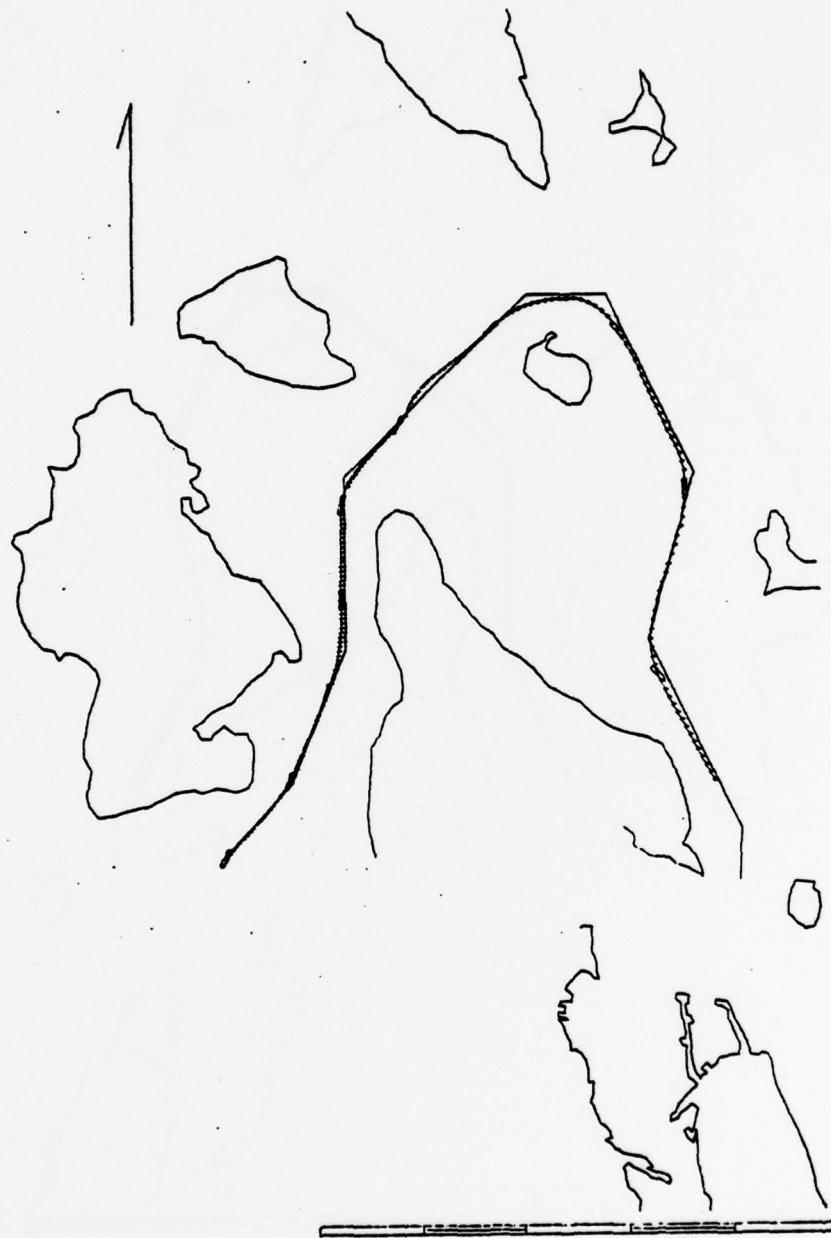


T 280 TYPE

BELLHM

U KT U WIND DIR U CRNT DIR

16.0 40.0 90.0 4.5 170.0 2.0 240.0



T400 TYPE

SELI M

U ST U WIND DIR. U CRNT DIR

10.0 40.0 90.0 4.5 190.0 2.0 240.0

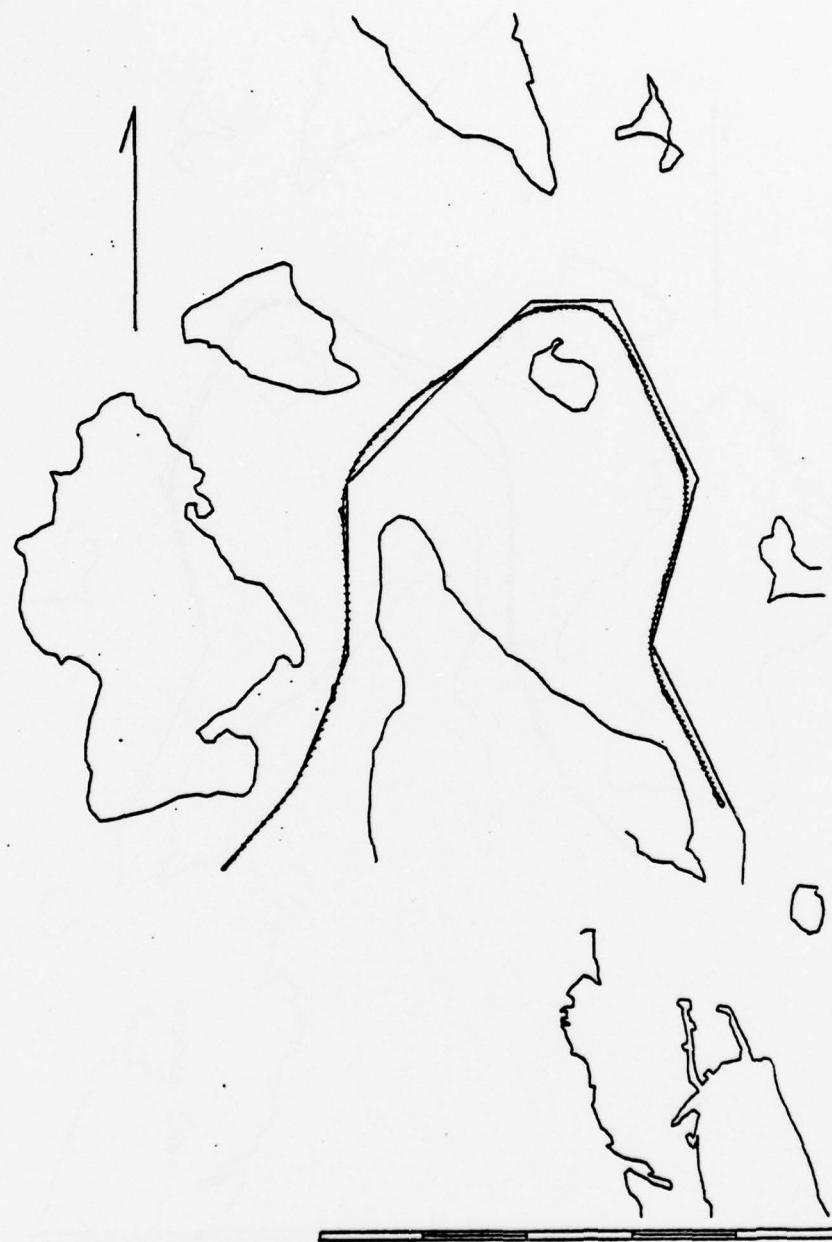


F 280 TYPE

RE-LIN

U CL U WIND OEP. U CNT OPR

8.0 40.0 270.0 4.0 45.0 1.5 310.0



1 290° 00'E

051.0 N

U CT U WIND DIP U CNT DIP

8.0 48.0 98.0 4.0 45.0 1.5 3.0.0

G-33



I 280TYPE

PEL'11

U-EF U WIND DIR U CNTD DIR

6.0 40.0 270.0 4.0 45.0 1.6 310.0

G-34



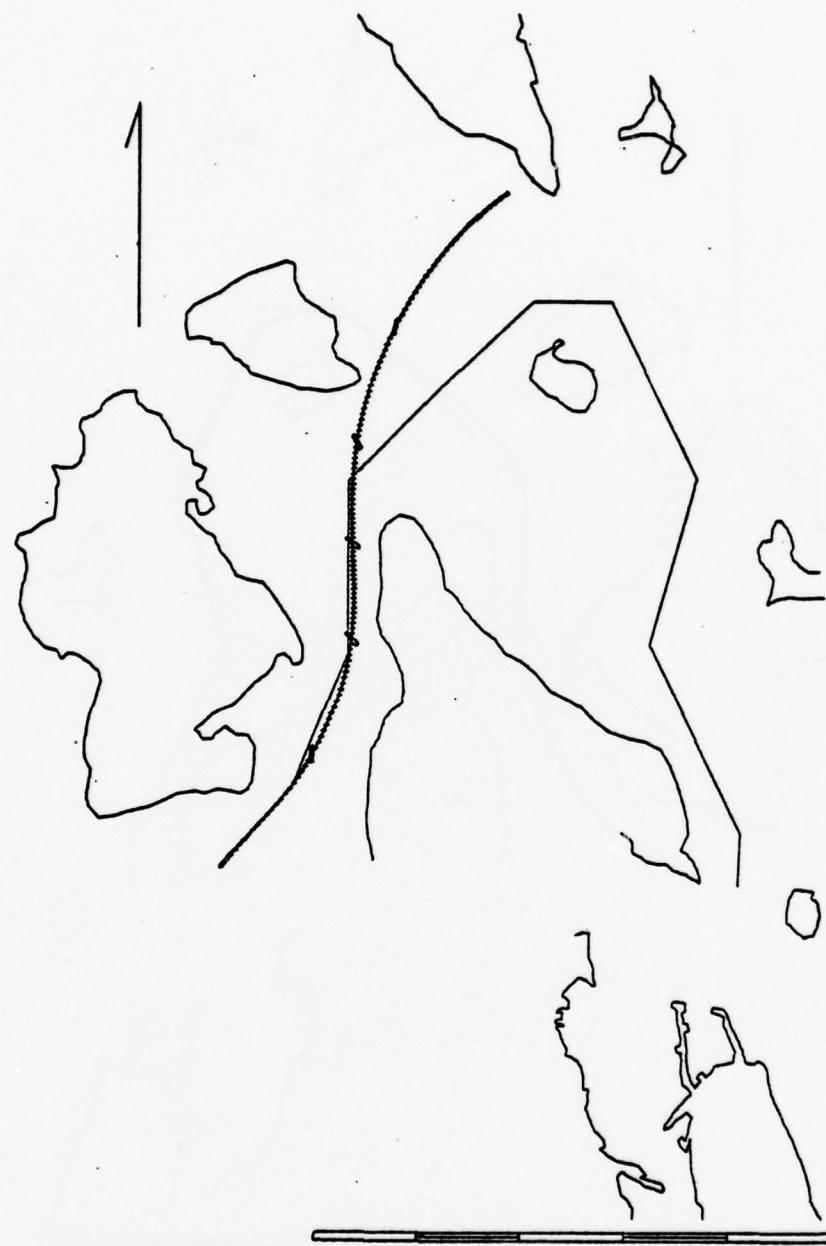
T 290725

ZULU

U CT U WIND DIR U CNT DIR

6.0 40.0 90.0 10 45.0 1.5 310.0

G-35



T 280TYPE

BELLINI

U ET U WIND DIR U CRNT DIR

4.0 40.0 270.0 4.0 45.0 1.5 310.0

G-36



T 280TYPE

BELLWHT

U ST U WIND DIR U CRNT DIR

4.0 46.0 90.0 4.0 45.0 1.5 310.0



T400 TYPE

RELM1

U ET U WIND DIP U CRNT DIR

10.0 40.0 270.0 4.5 199.0 2.0 249.0

G-38



-1400 TYPE

BELM1

U ET U WIND DIR U CRNT DIR

10.0 40.0 90.0 4.5 140.0 2.0 240.0



1400 TIME

EDM1

U CT U WIND DIR U CRNF DIR

8.0 40.0 270.0 1.0 45.0 1.0 310.0

G-40



T400 TYPE

SELHM

U E1 U WIND DIR U CANT DIR

8.0 40.0 90.0 4.0 45.0 1.5 310.0

G-41



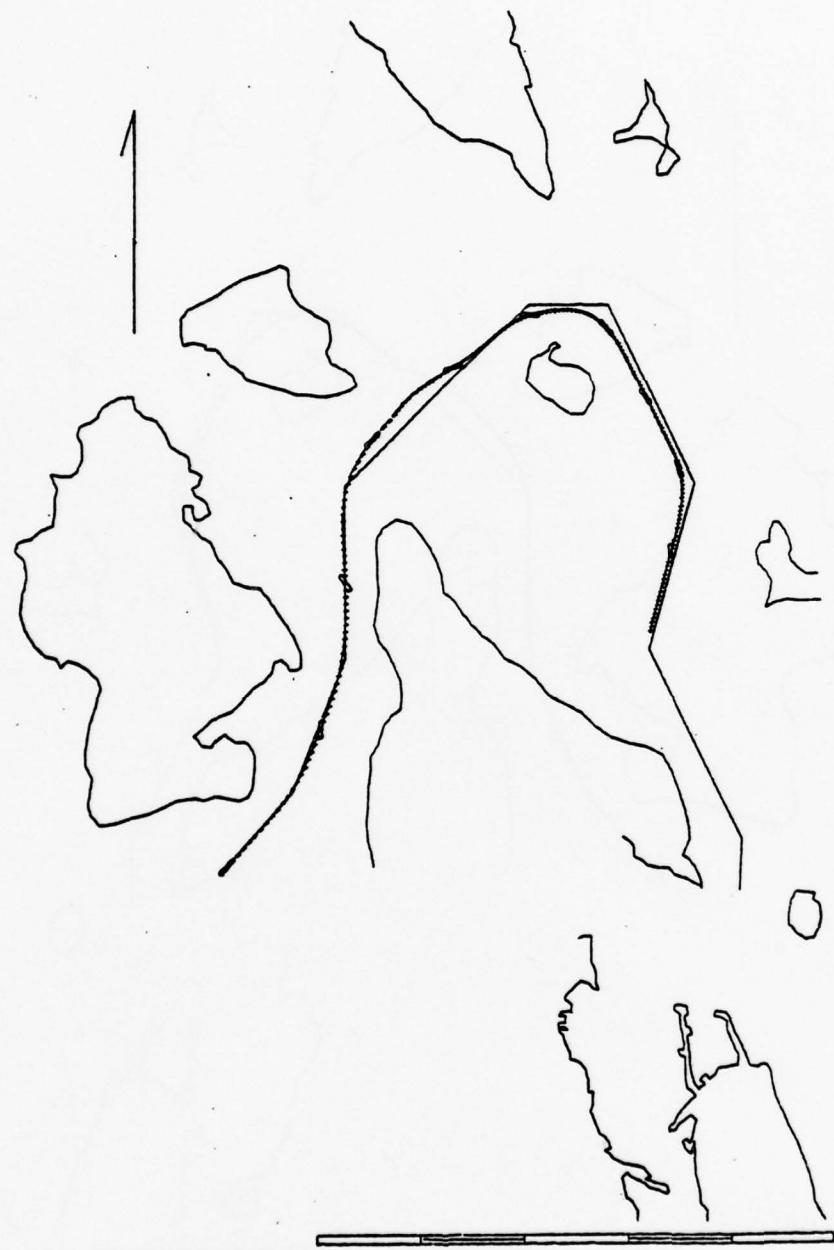
F400 TYPE

DELTA

U ET U WIND DIR U CPNT DIP

6.0 40.0 270.0 4.0 45.0 1.5 310.0

G-42



T400 TYPE

SEJH1

U KT U WIND DIR U CRNT DIR

6.0 -10.0 90.0 1.0 -45.0 1.5 210.0

G-43



TAOB TYPE

BELT#1

U ET U WIND DIR U CPNT DIP

6.0 40.0 270.0 4.0 45.0 1.5 310.0

G-44



T408 TYPE

BELM

U ET U WIND DIR U CNT DIR

4.0 40.0 270.0 4.0 45.0 1.5 310.0

G-45



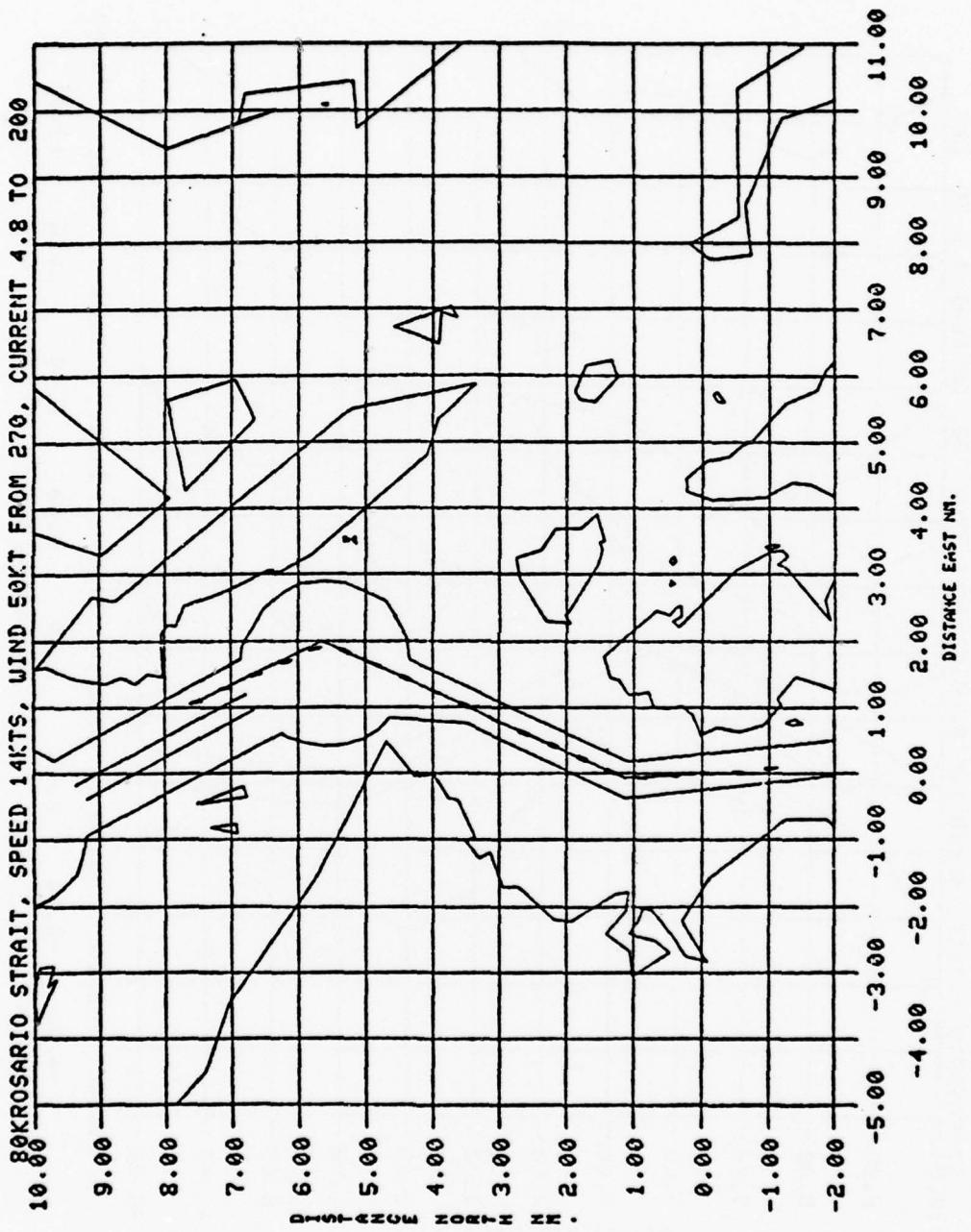
T400 TYPE

BELM1

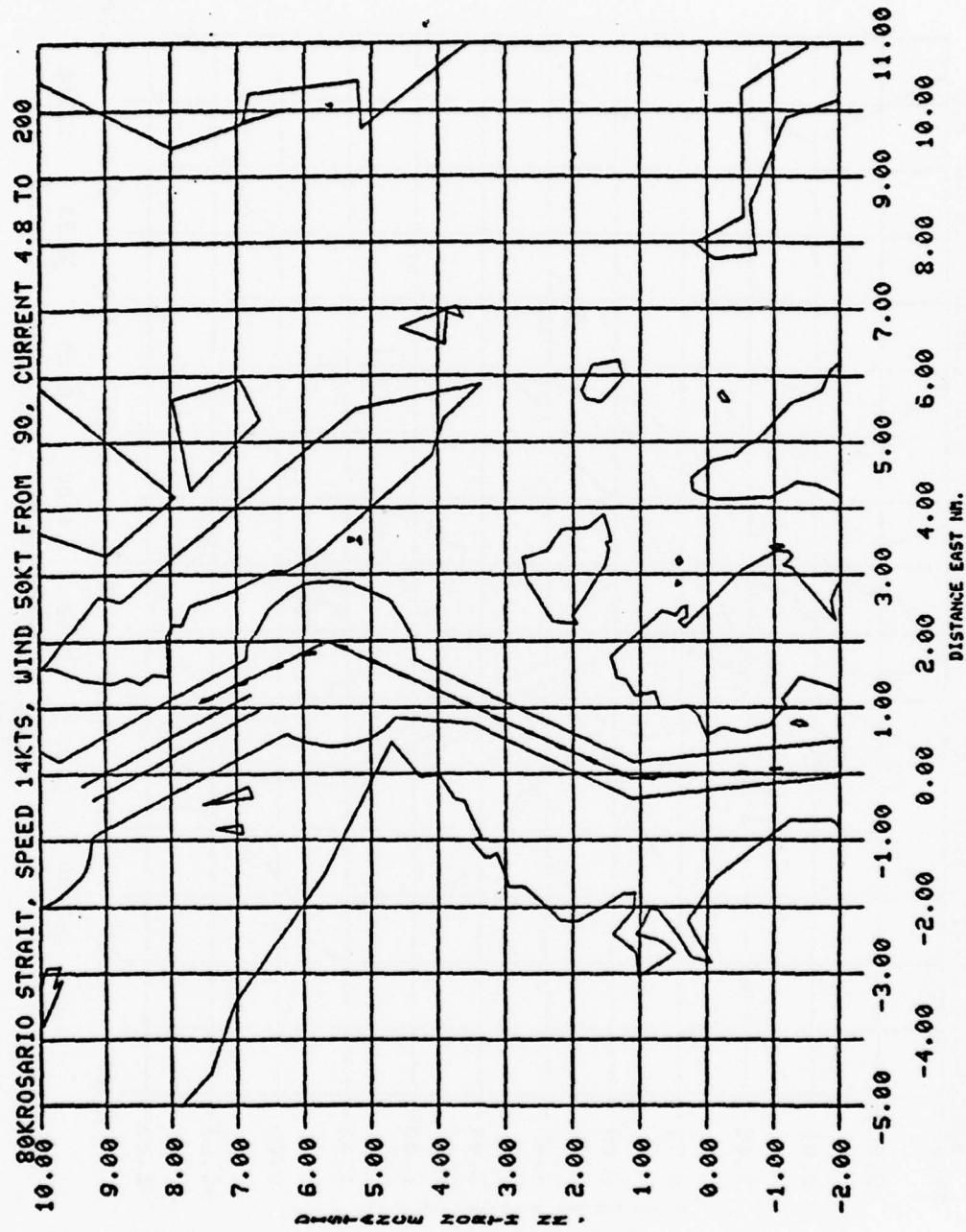
U KT U WIND DIR U CRNT DIR

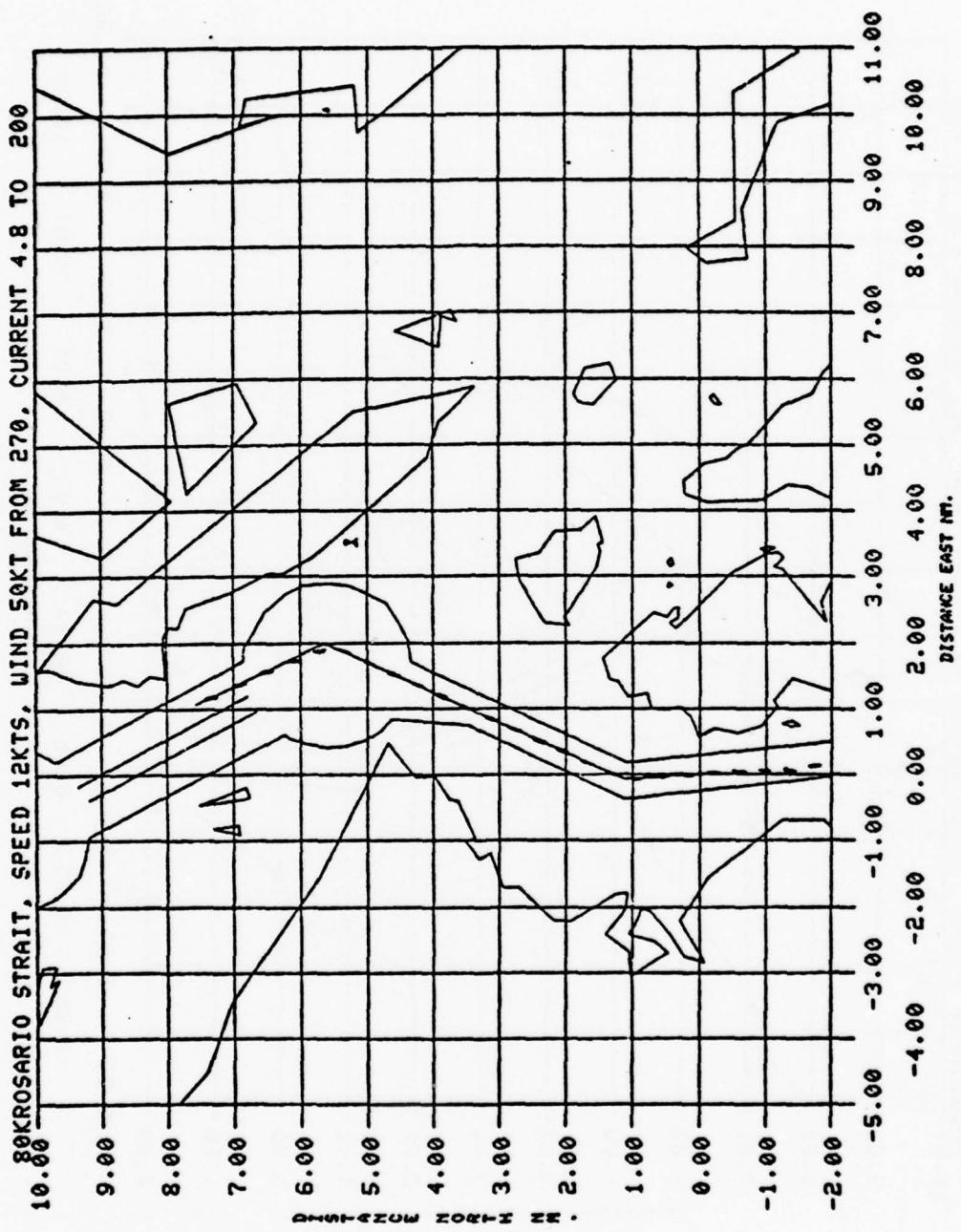
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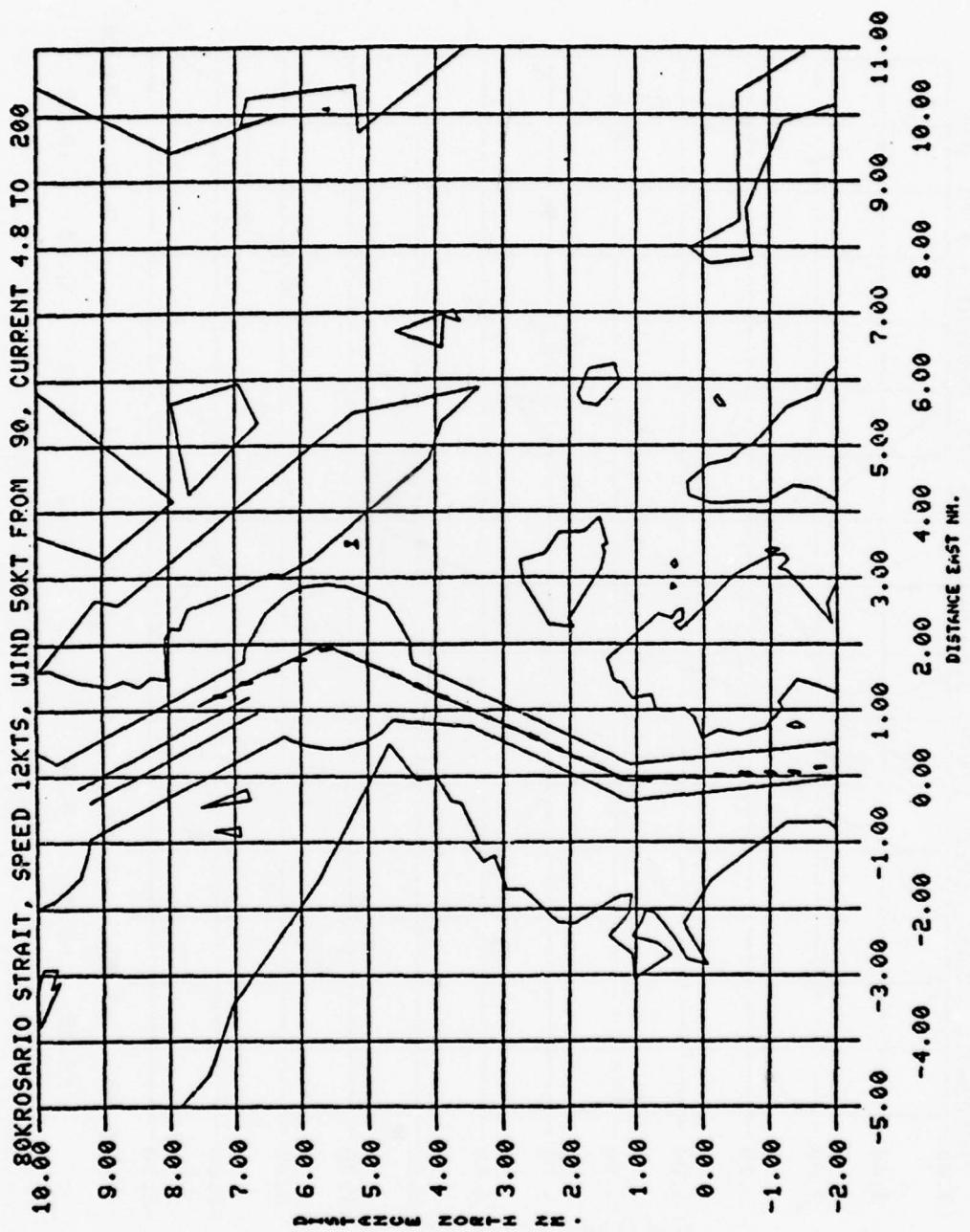
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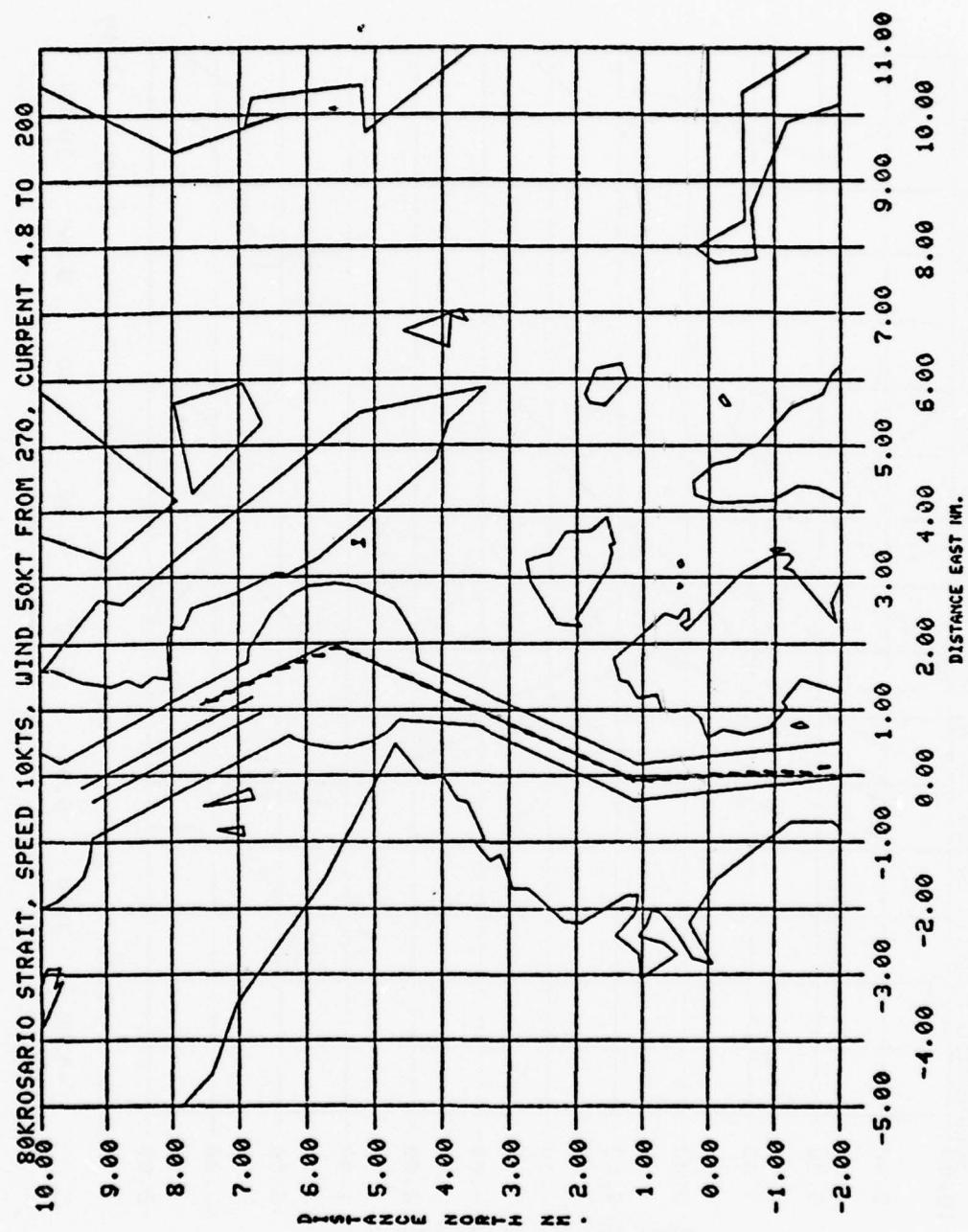


G-47

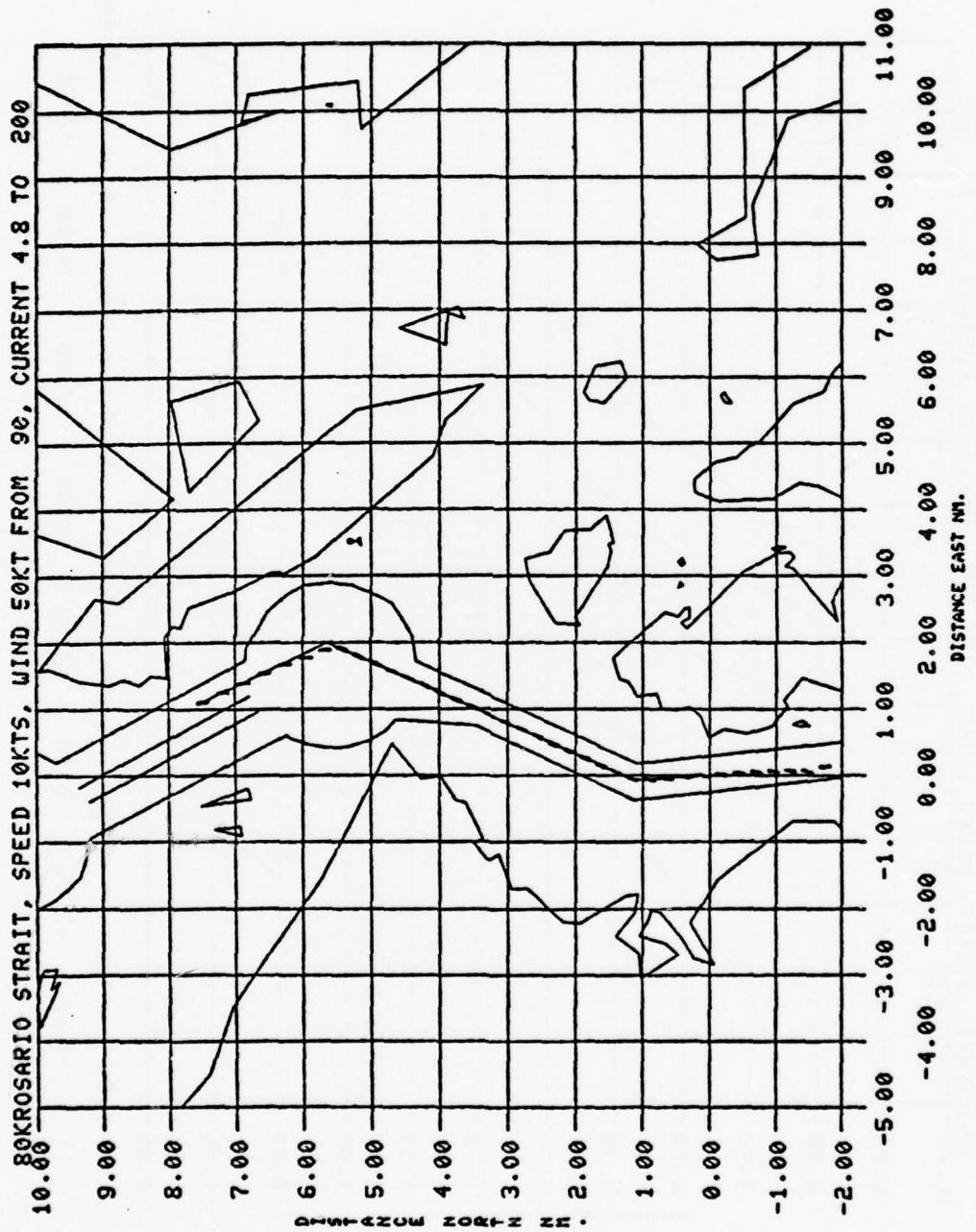




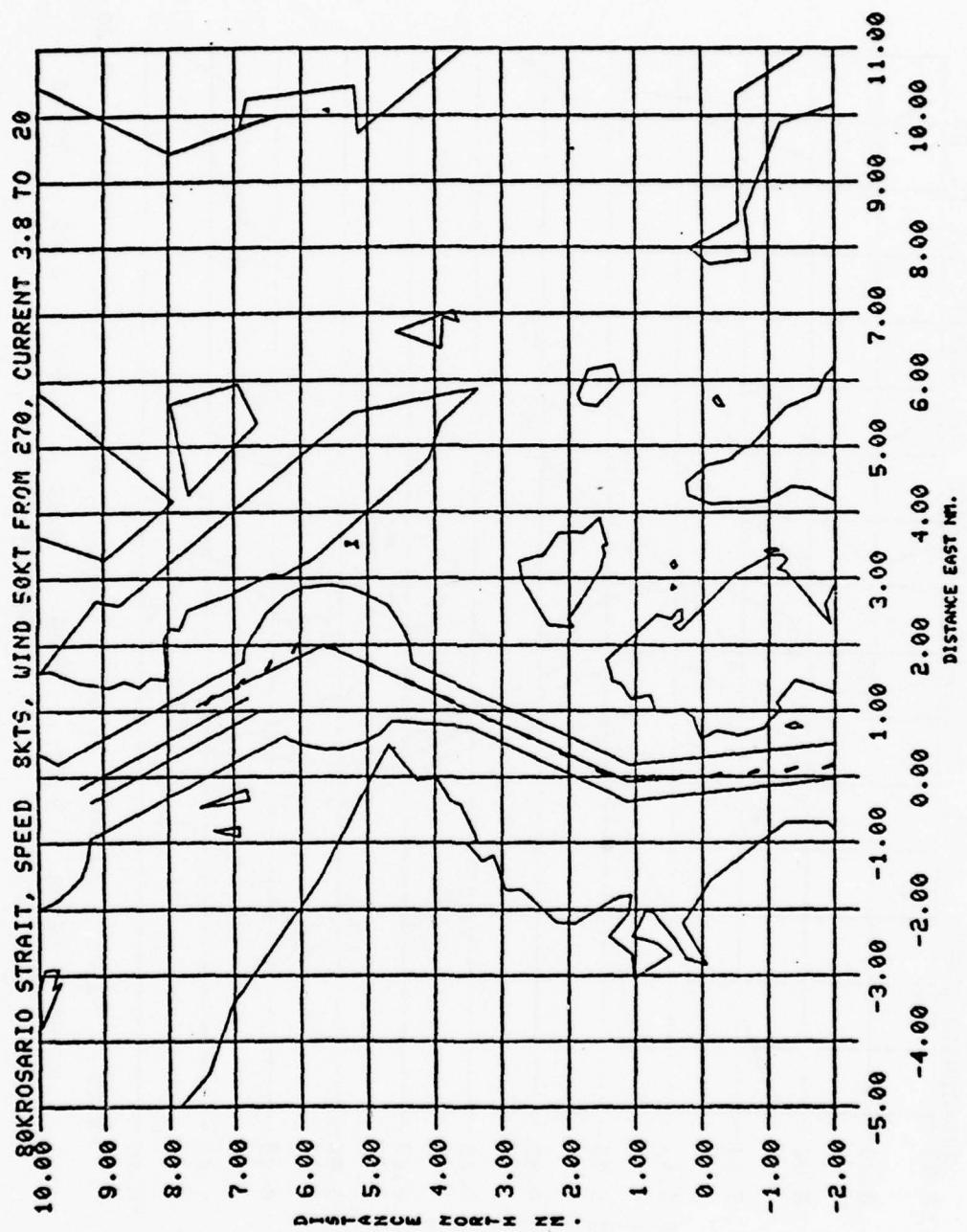




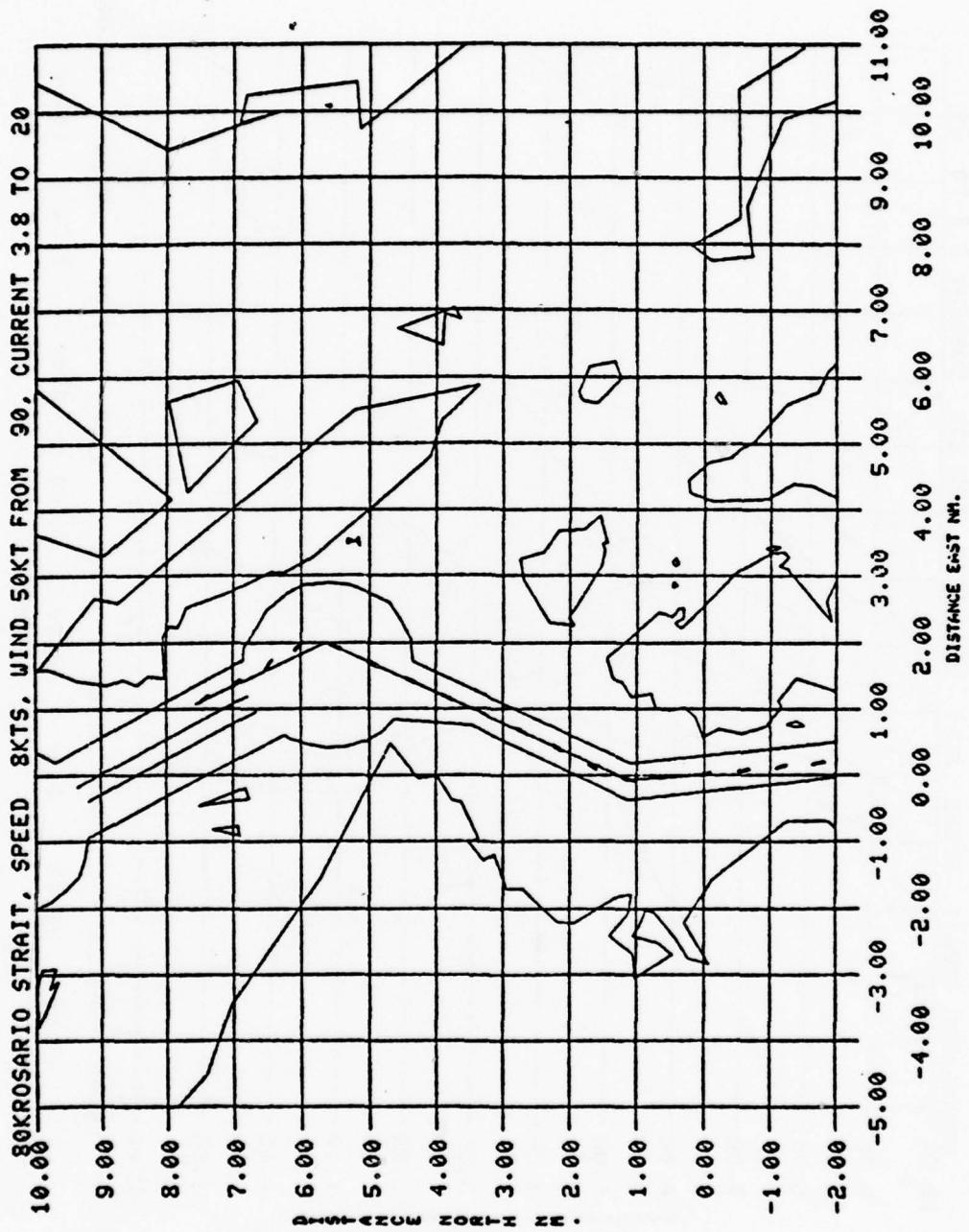
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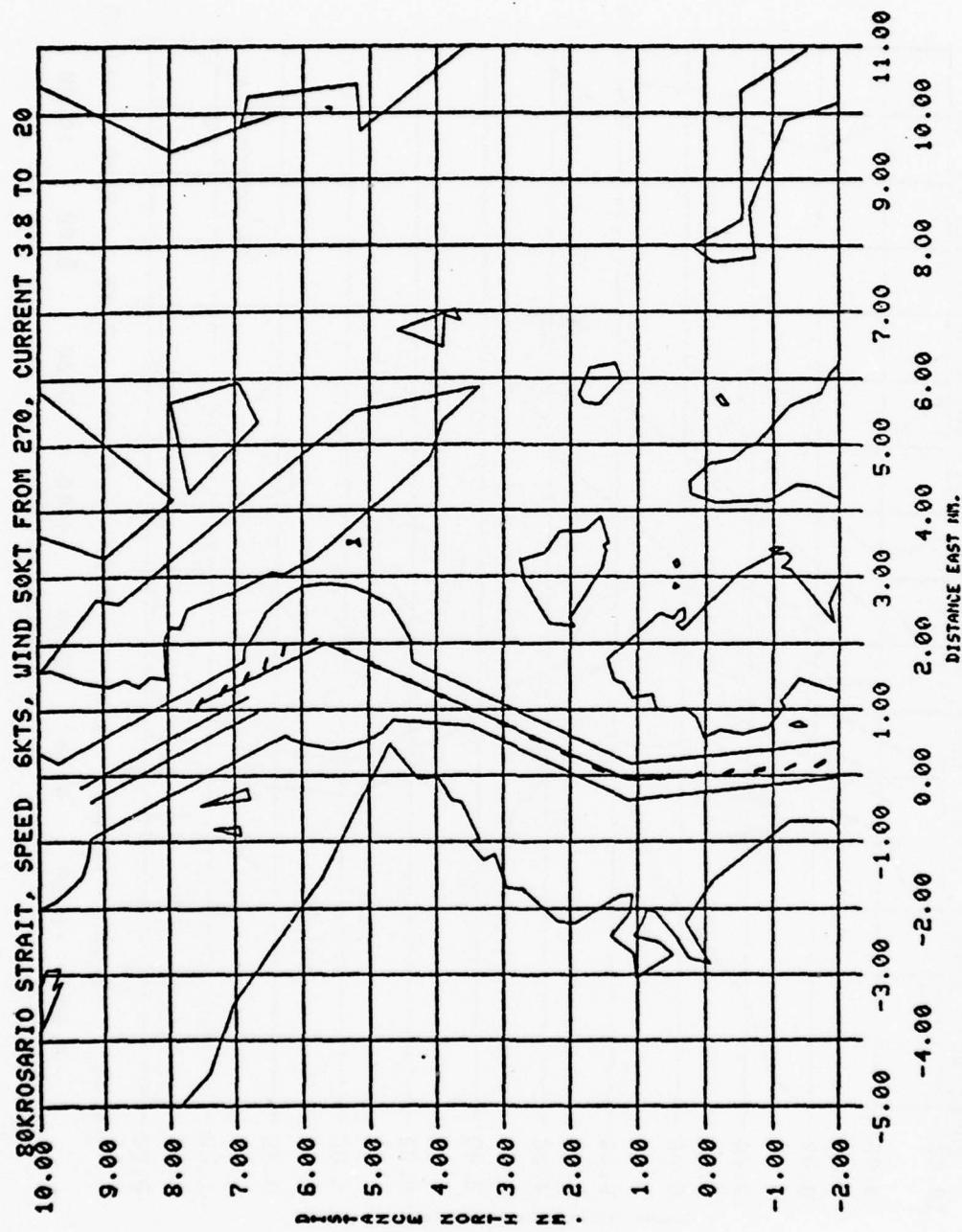


G-52

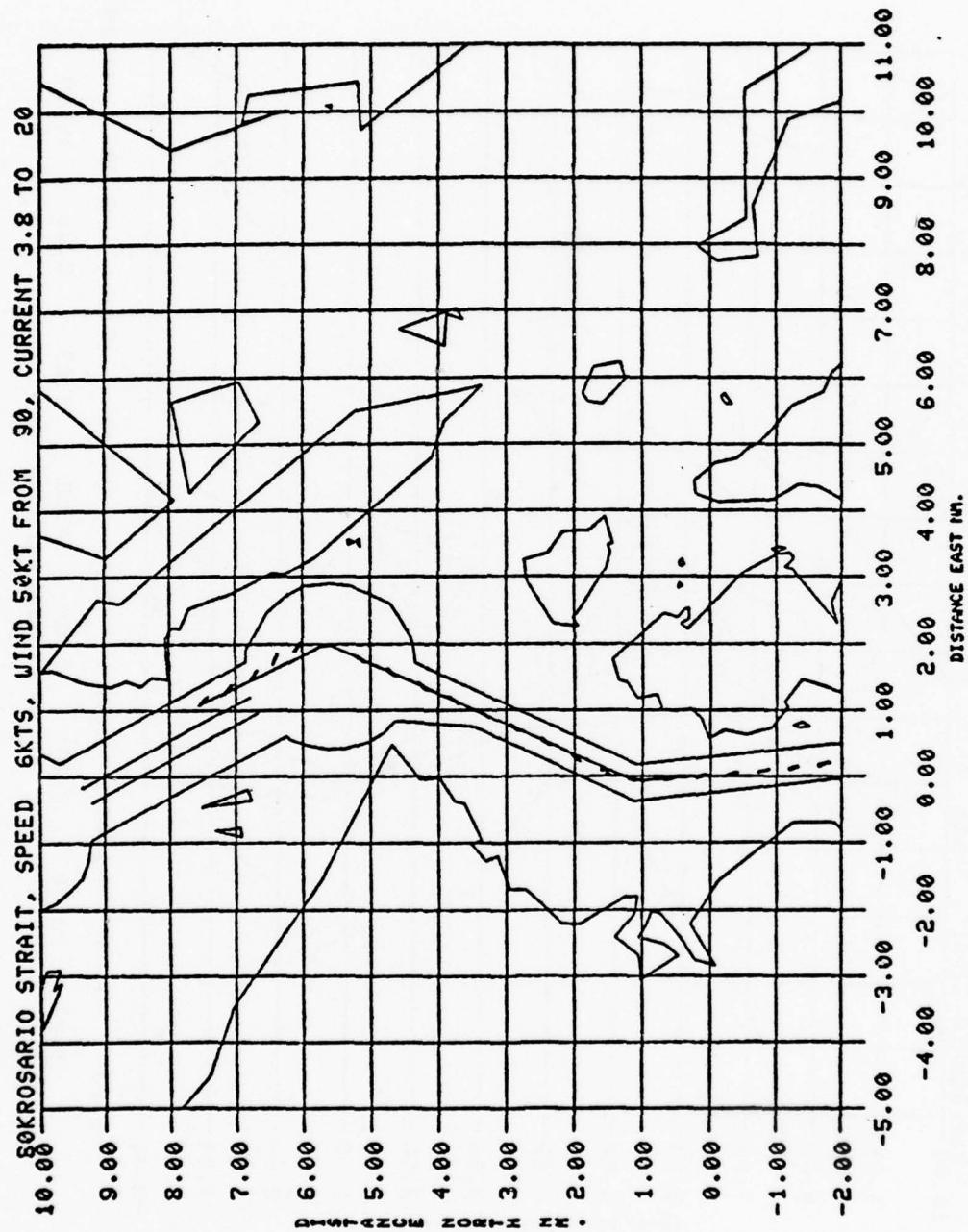


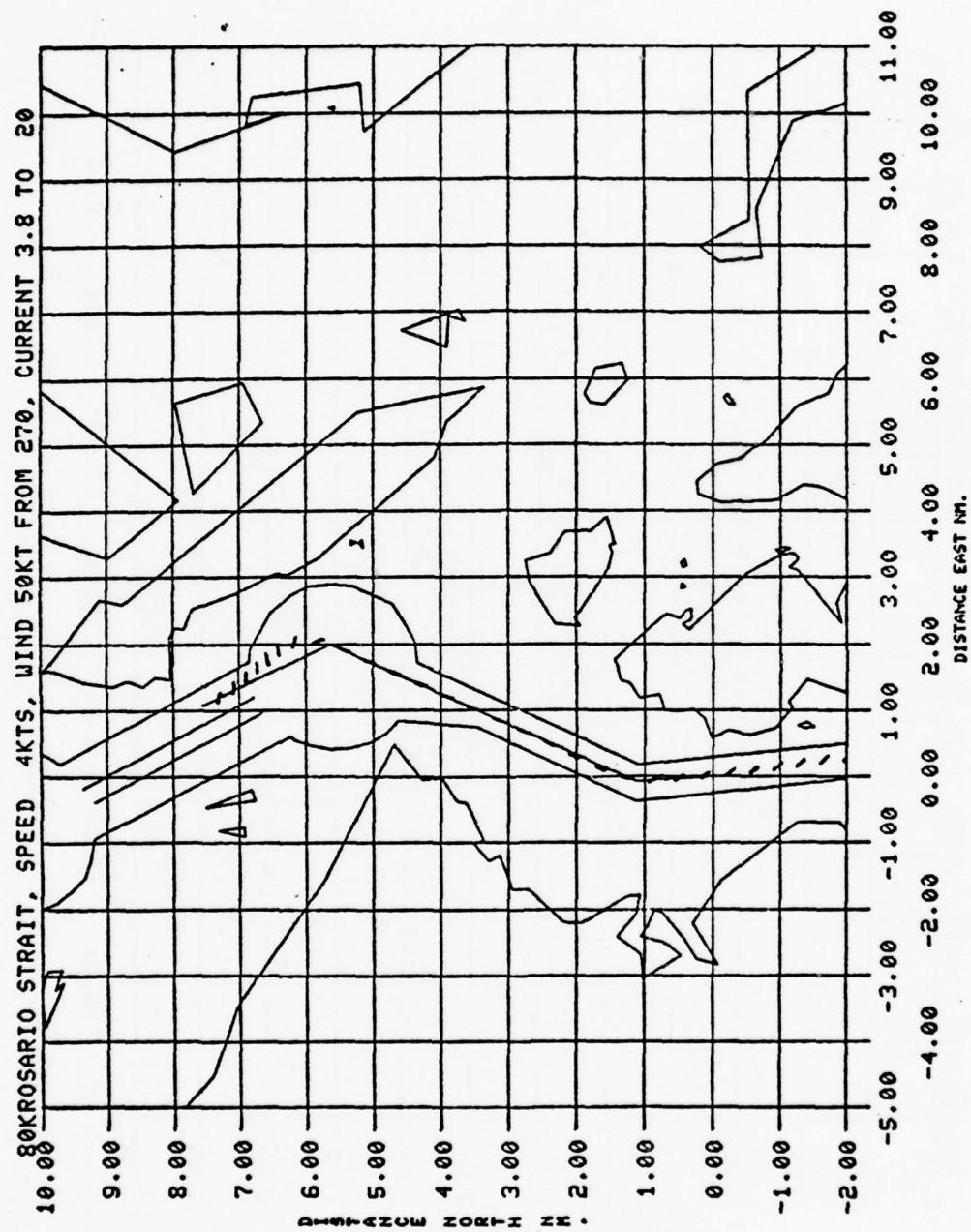
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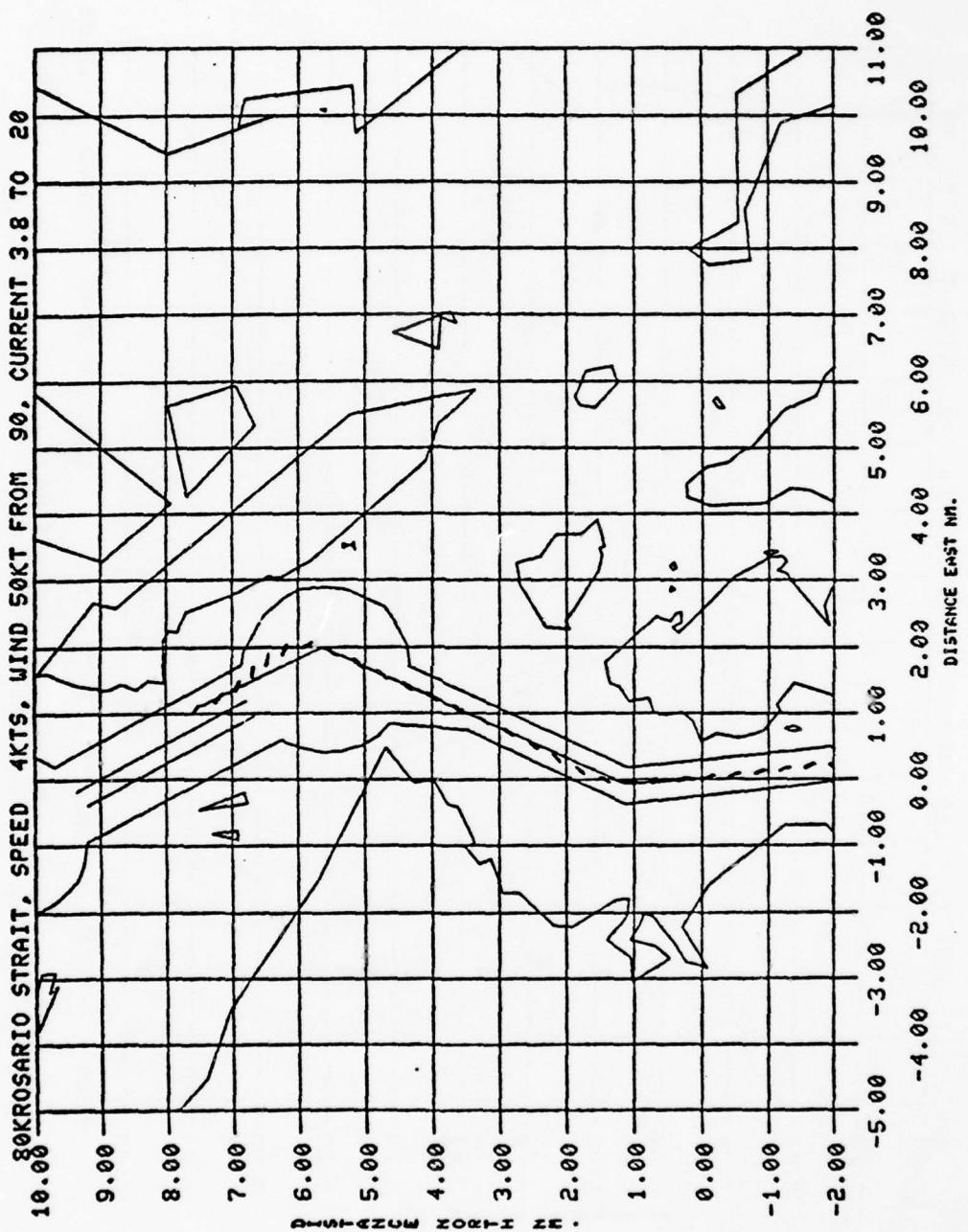


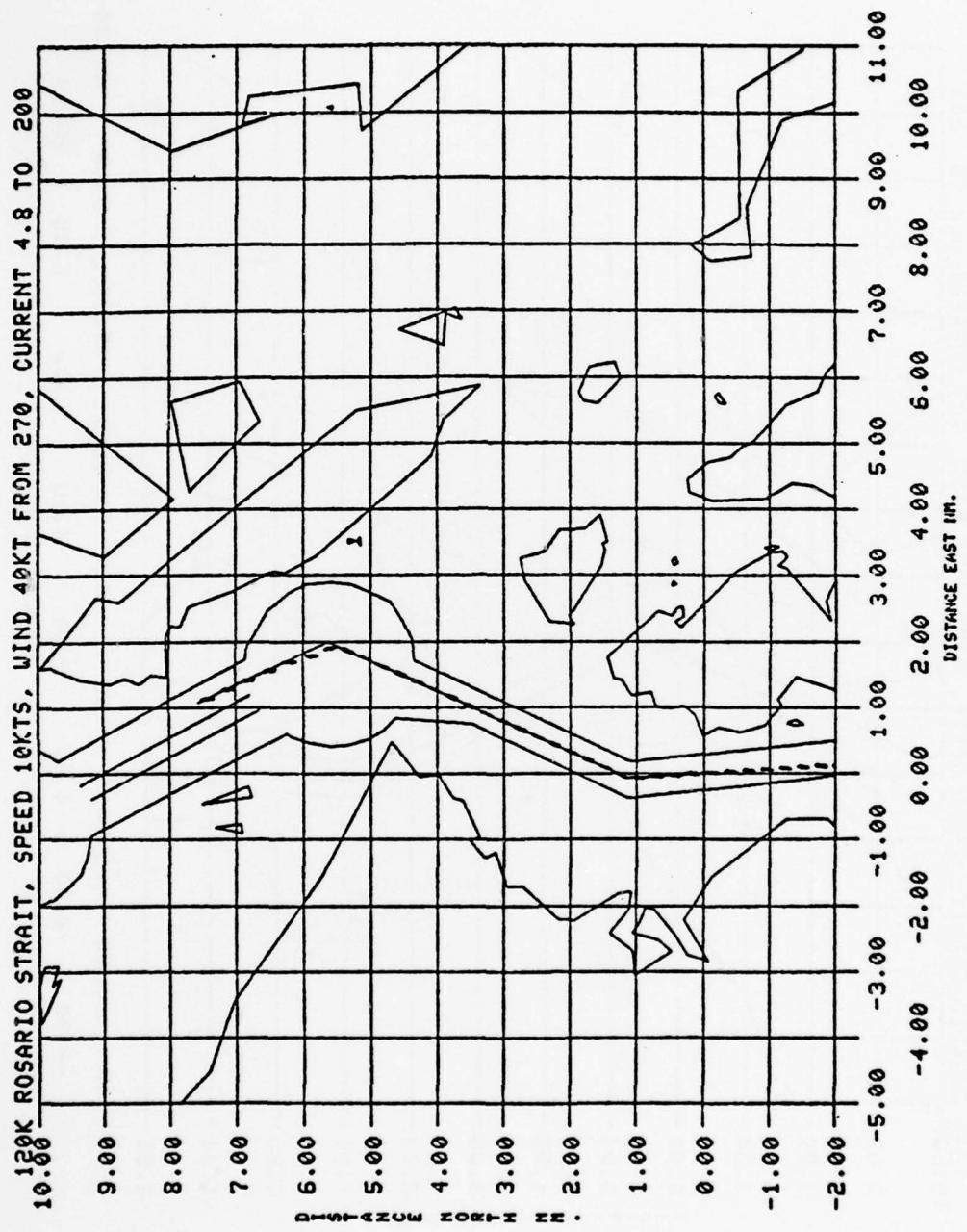


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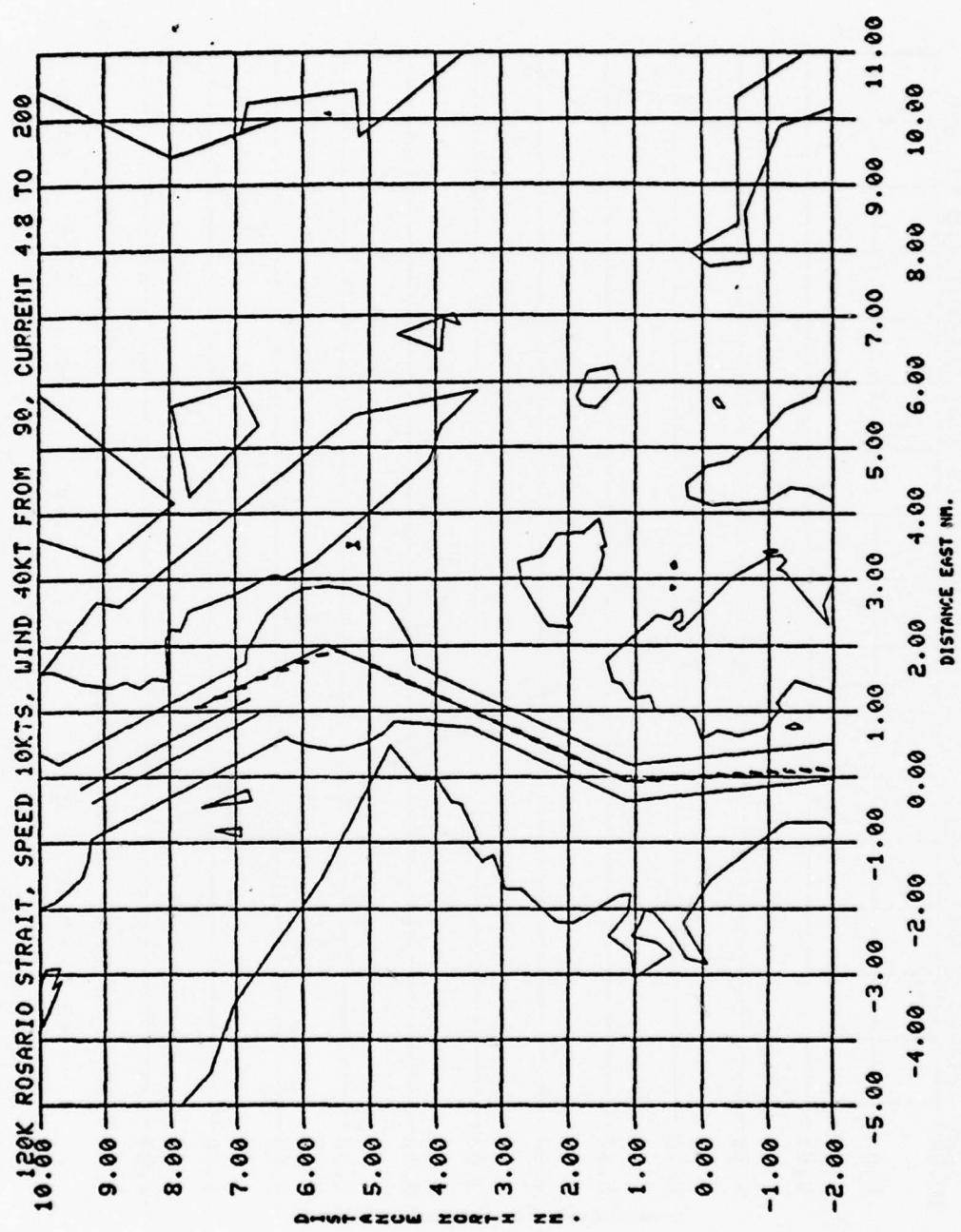


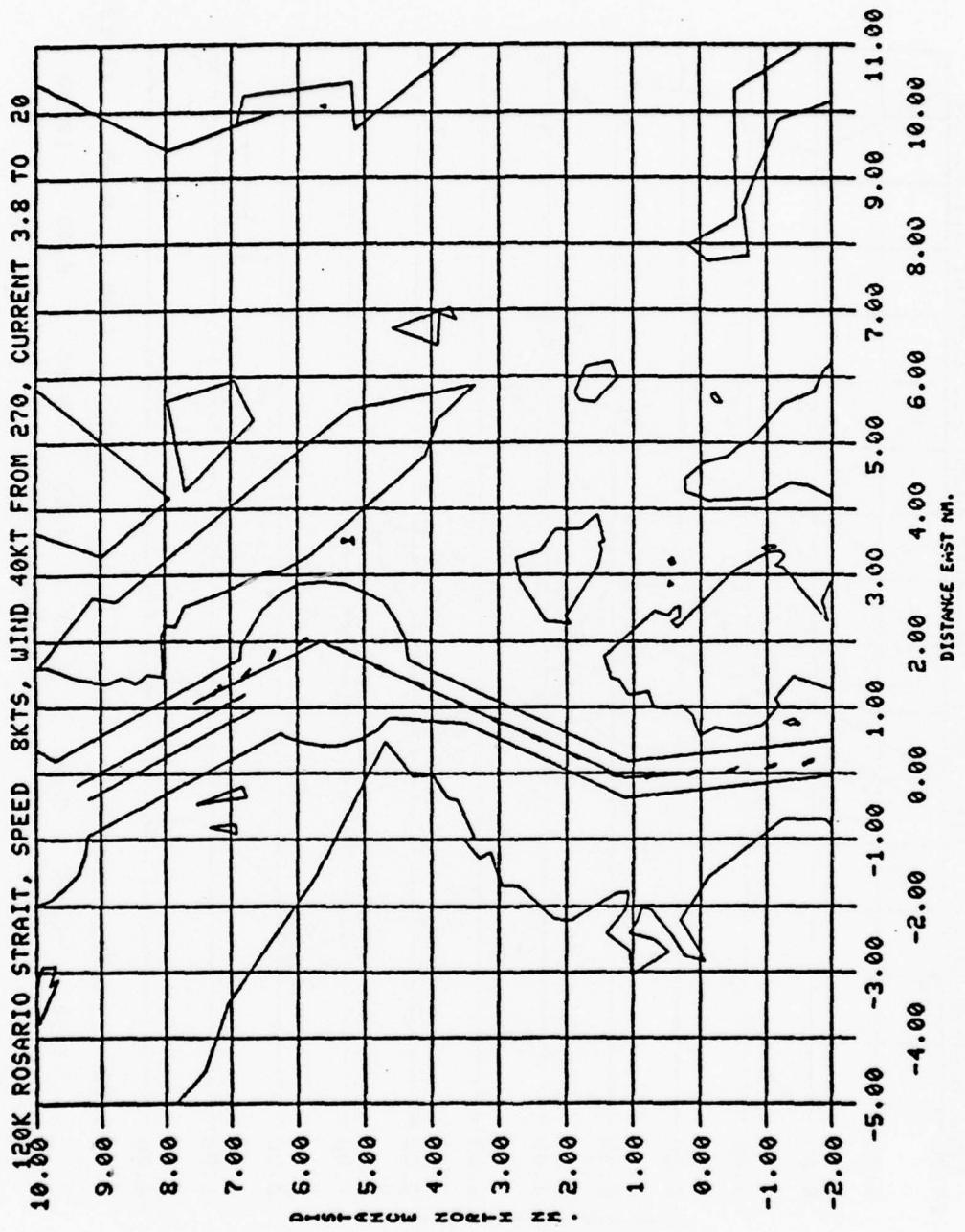


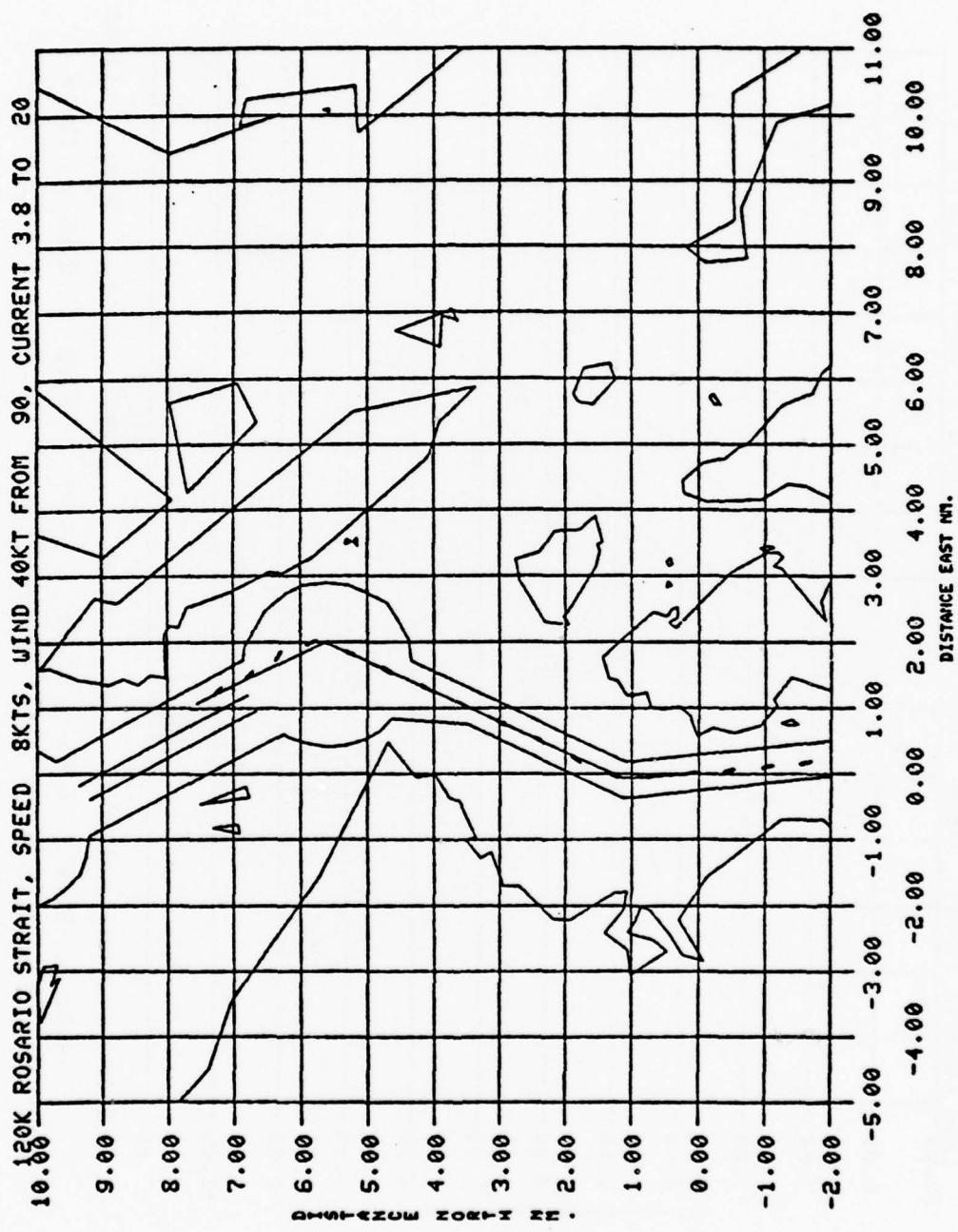


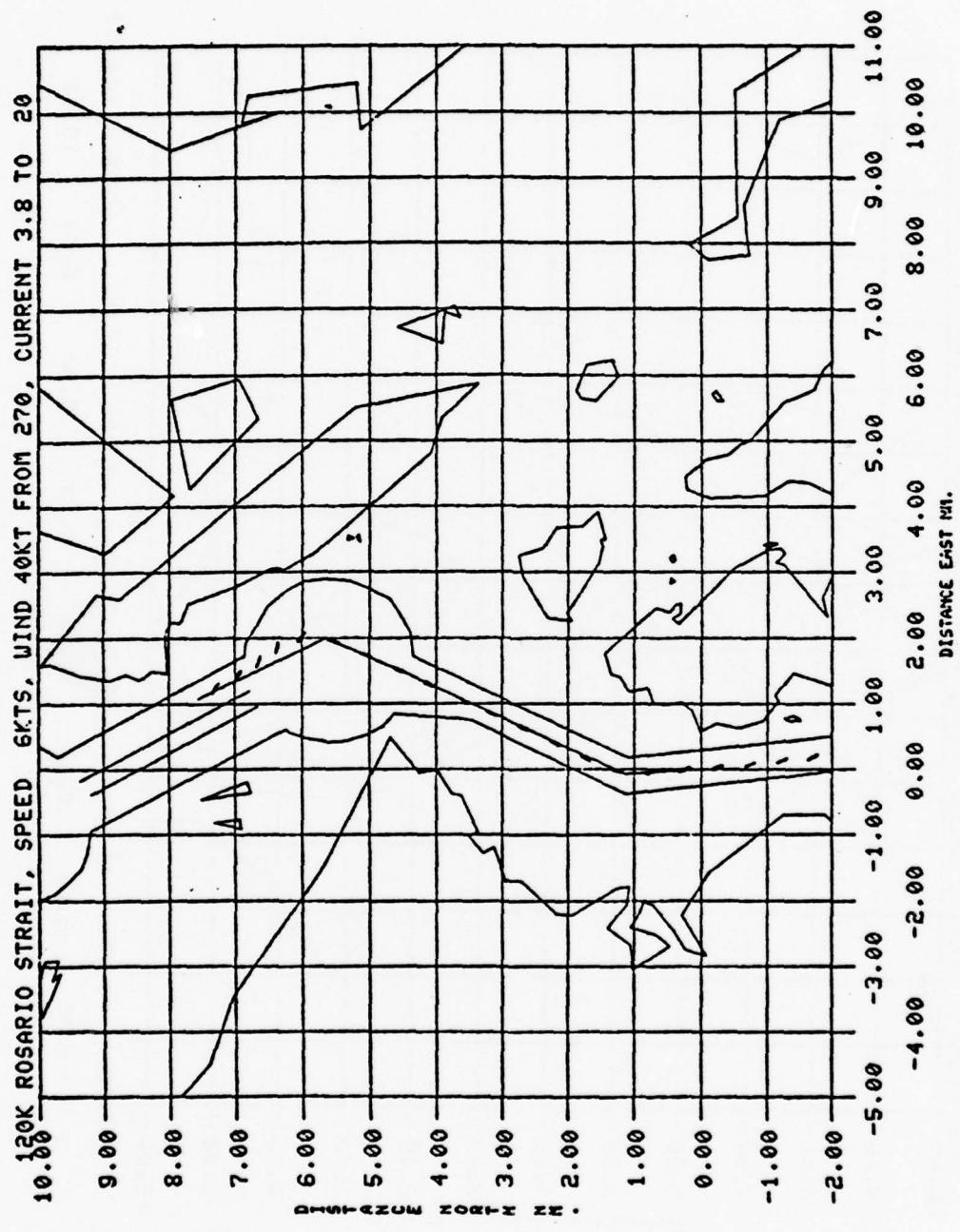


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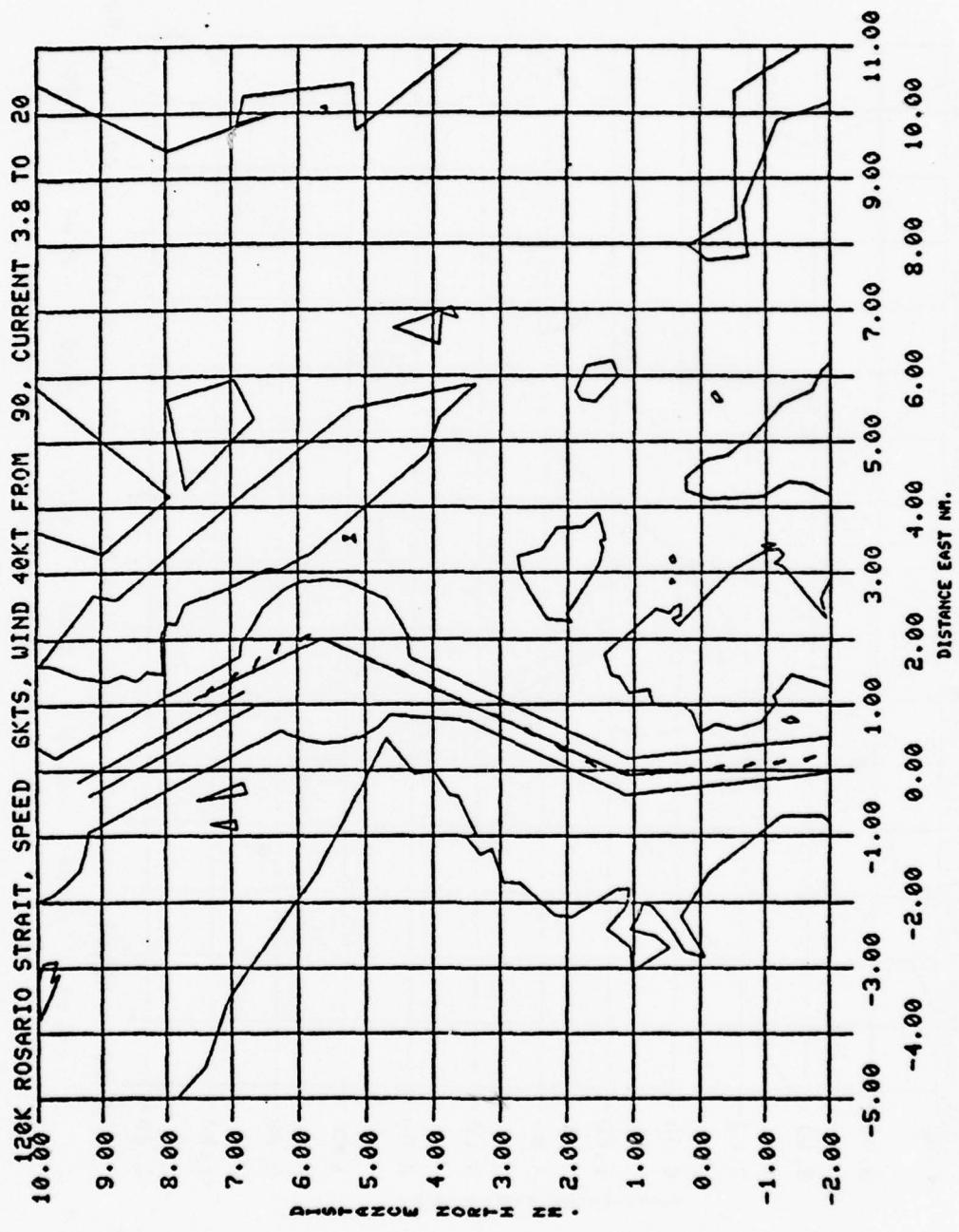


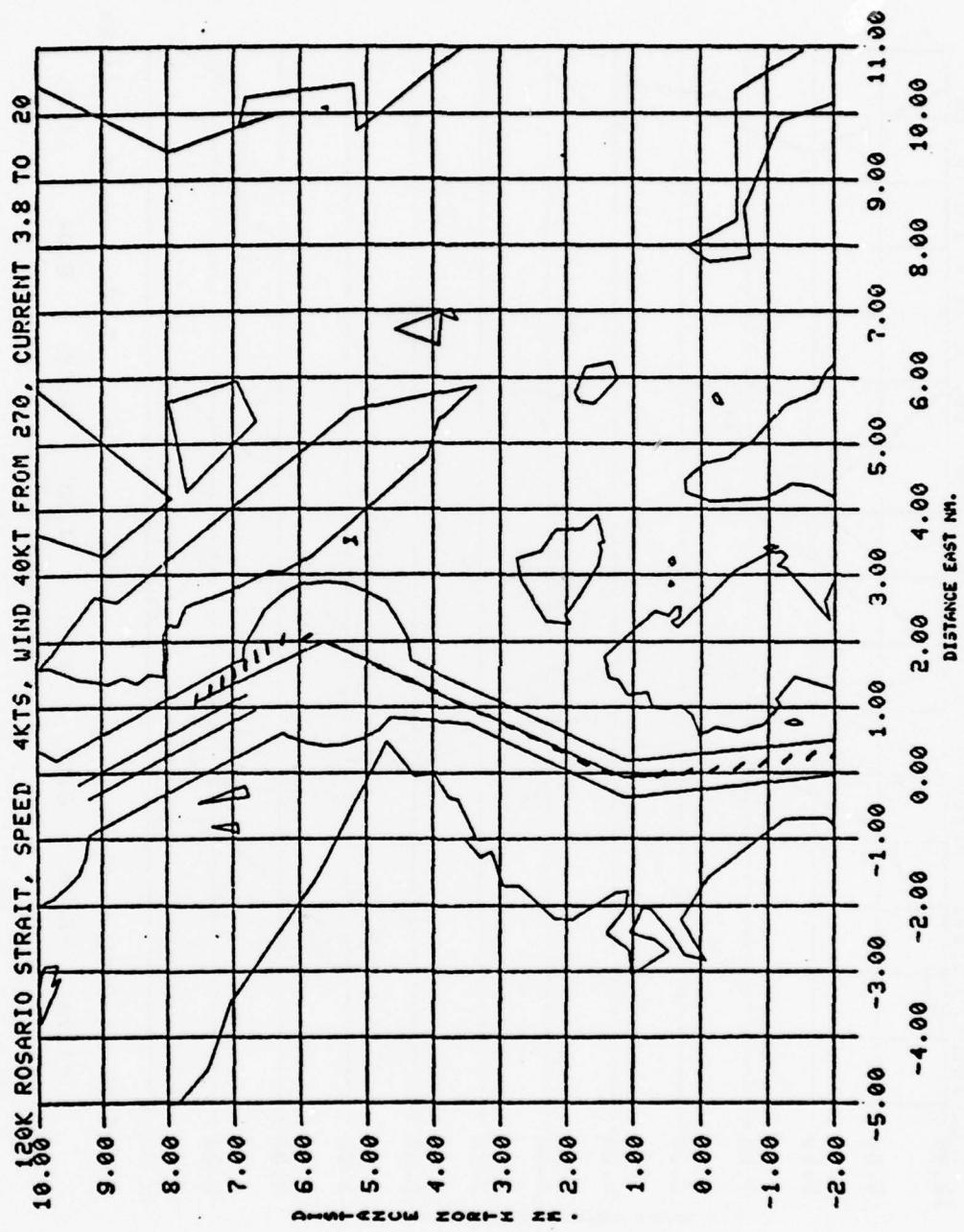




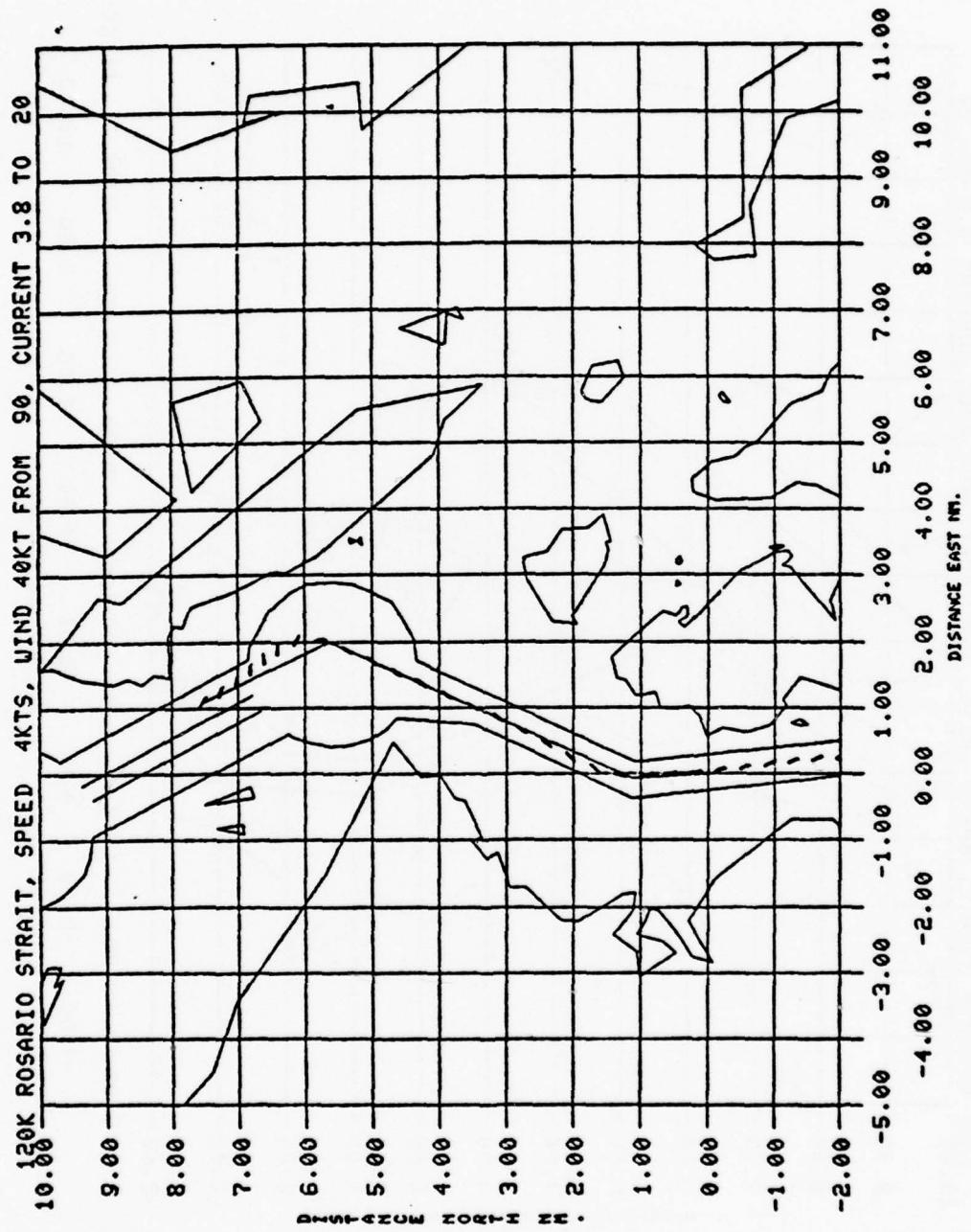


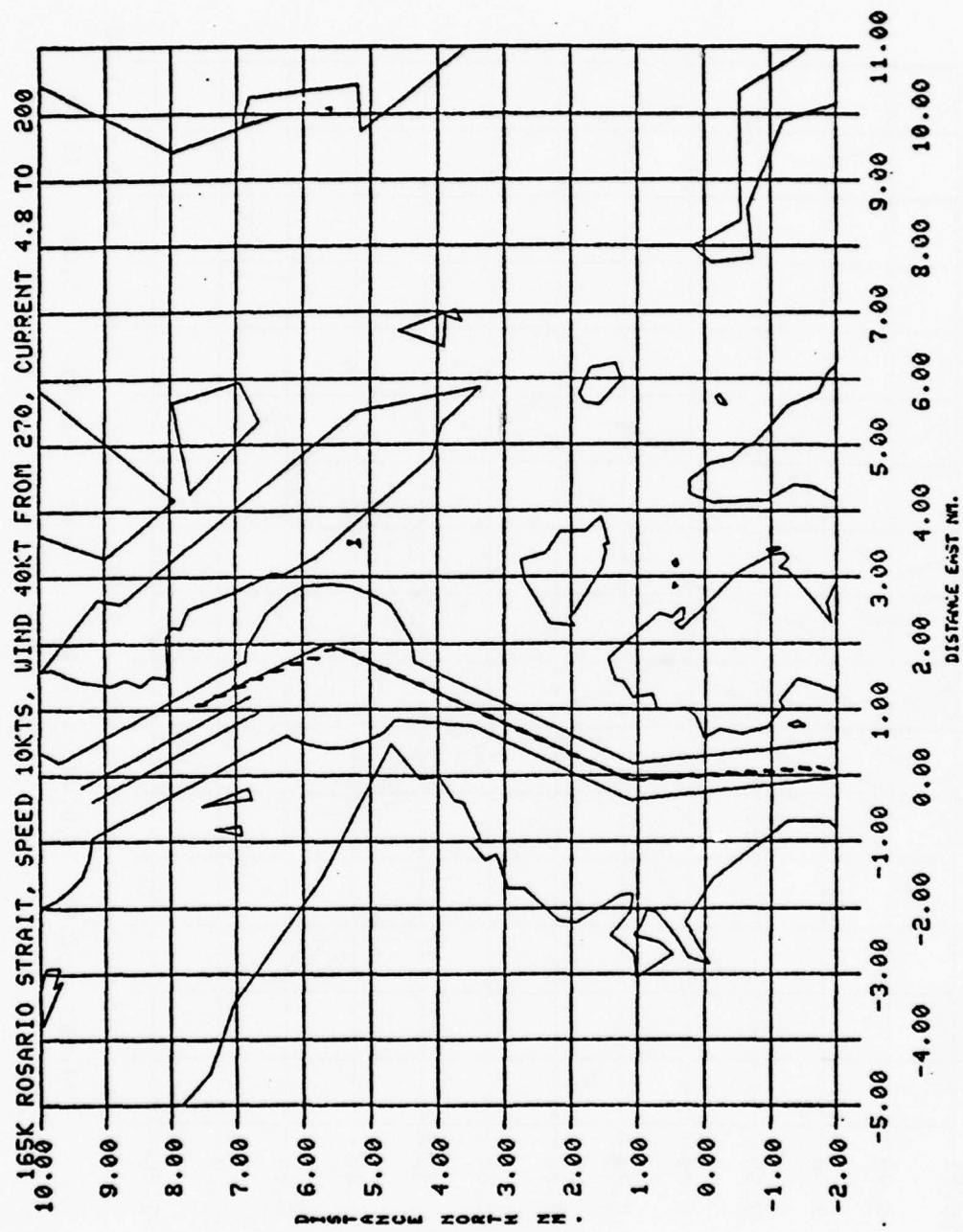
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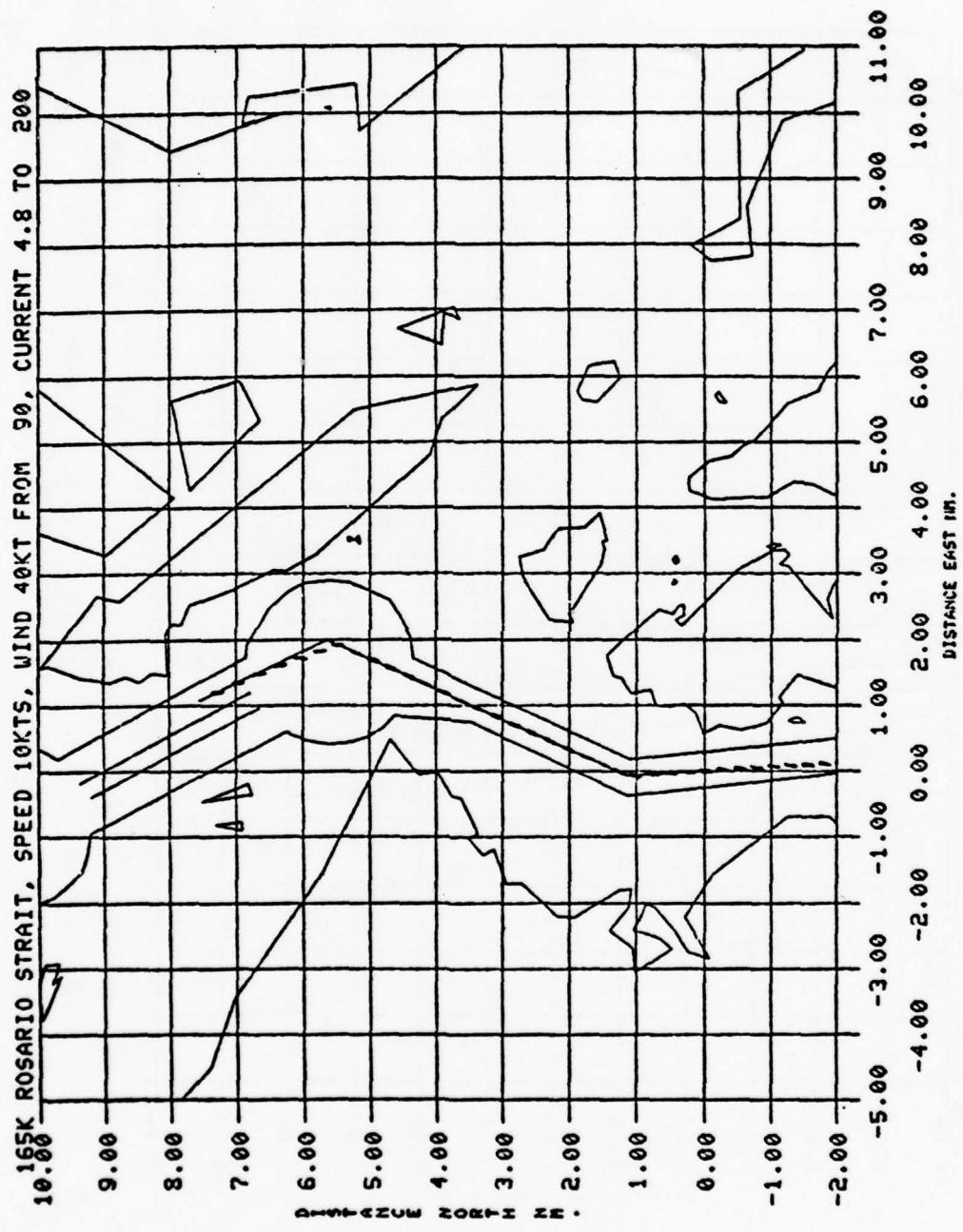


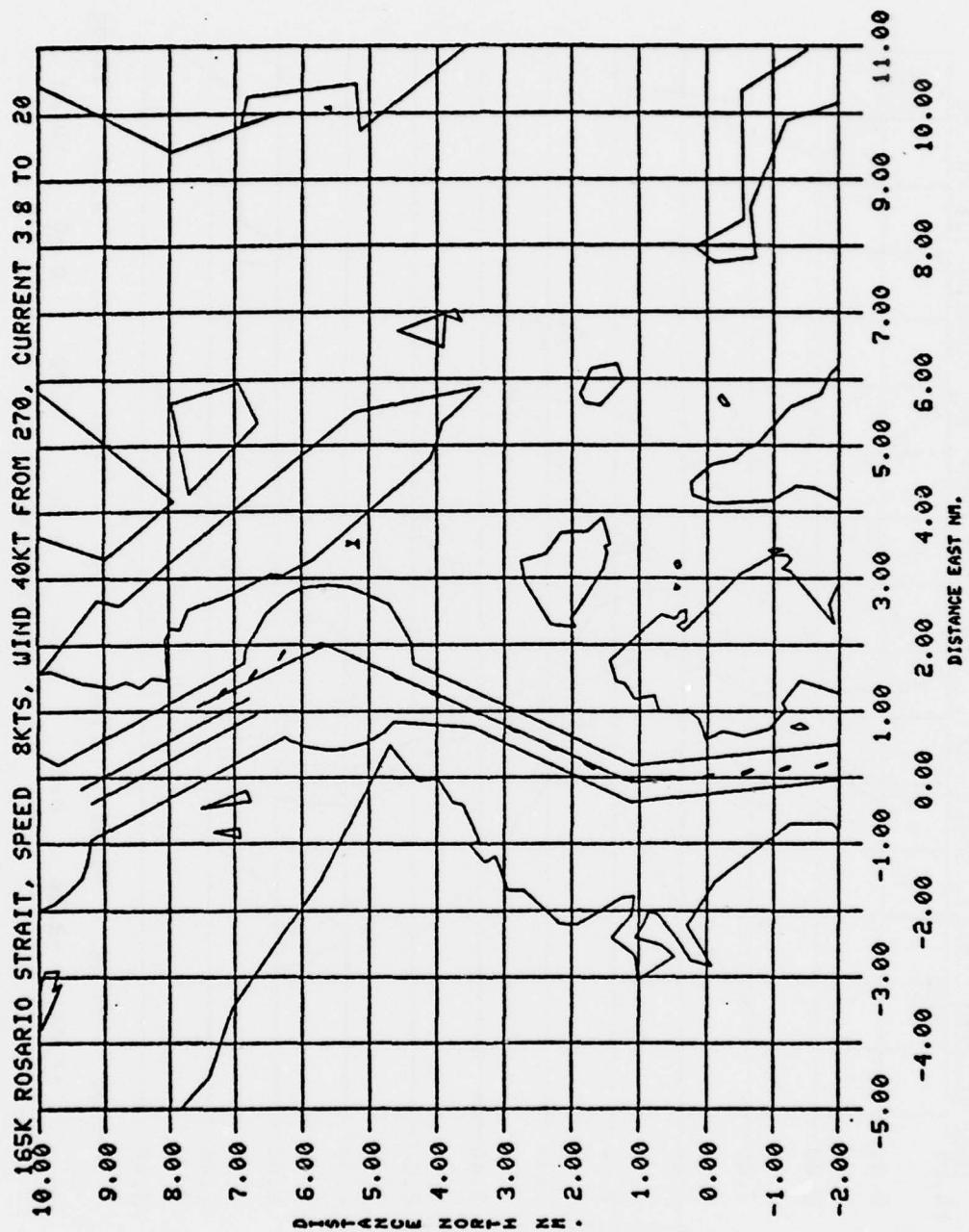
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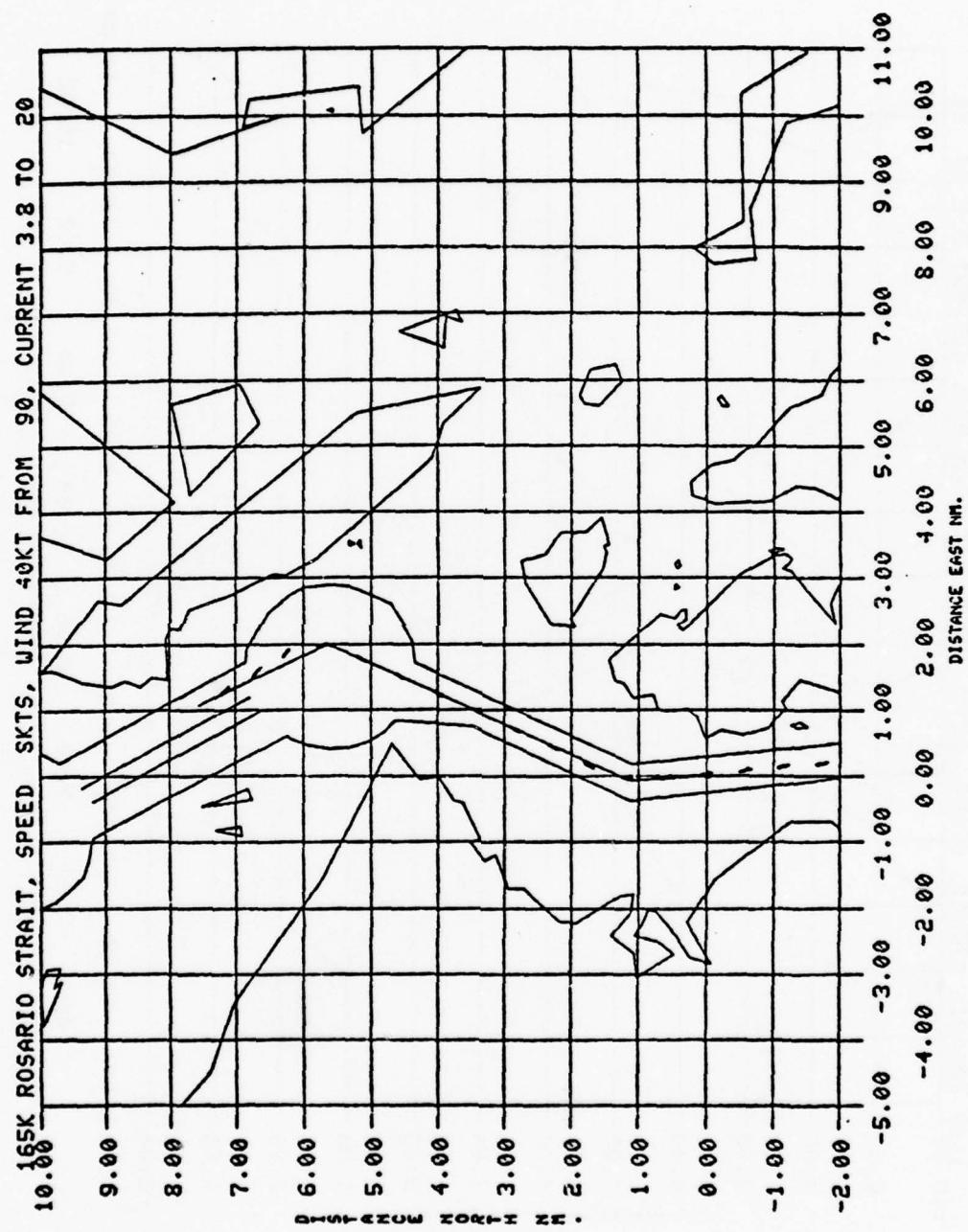


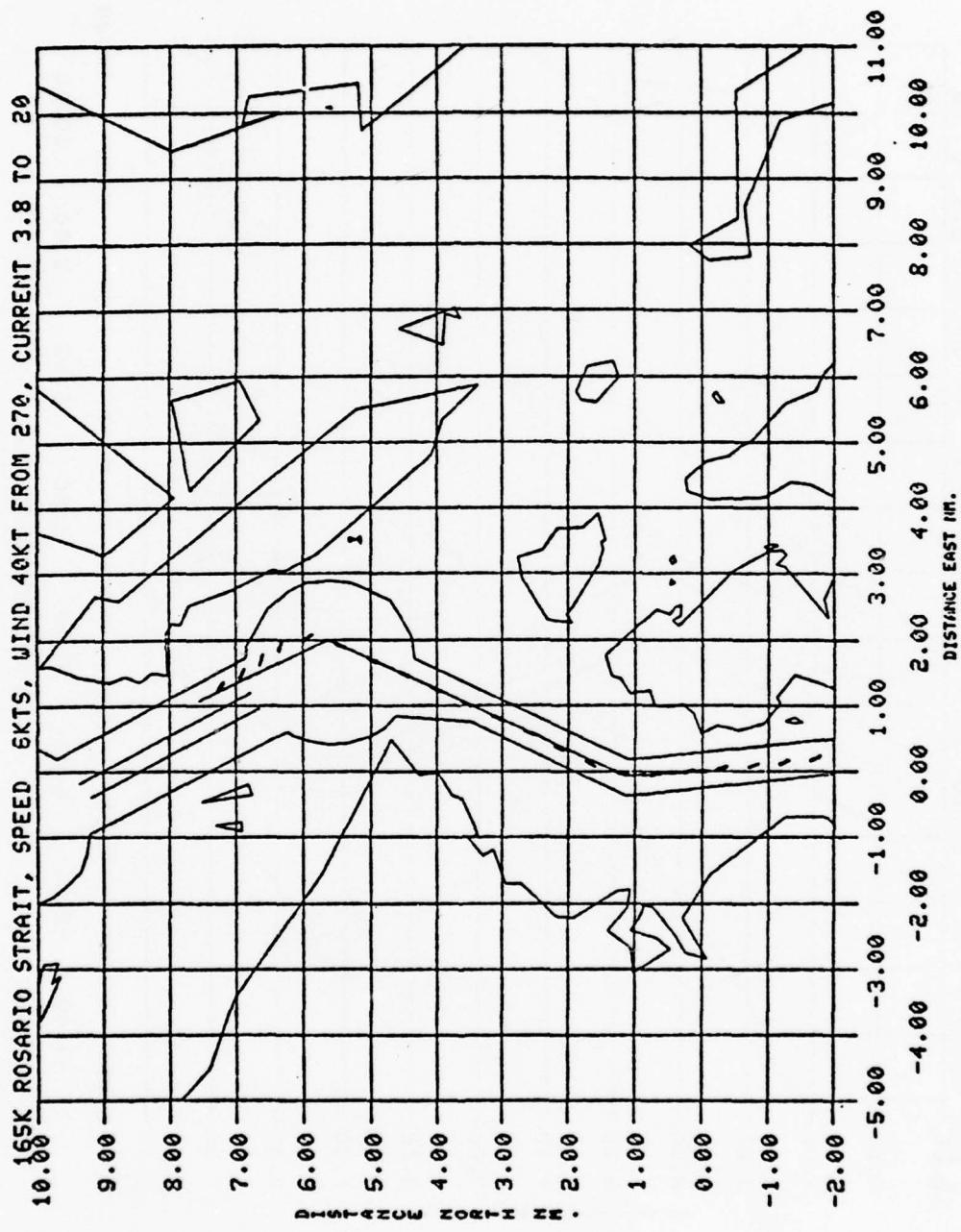


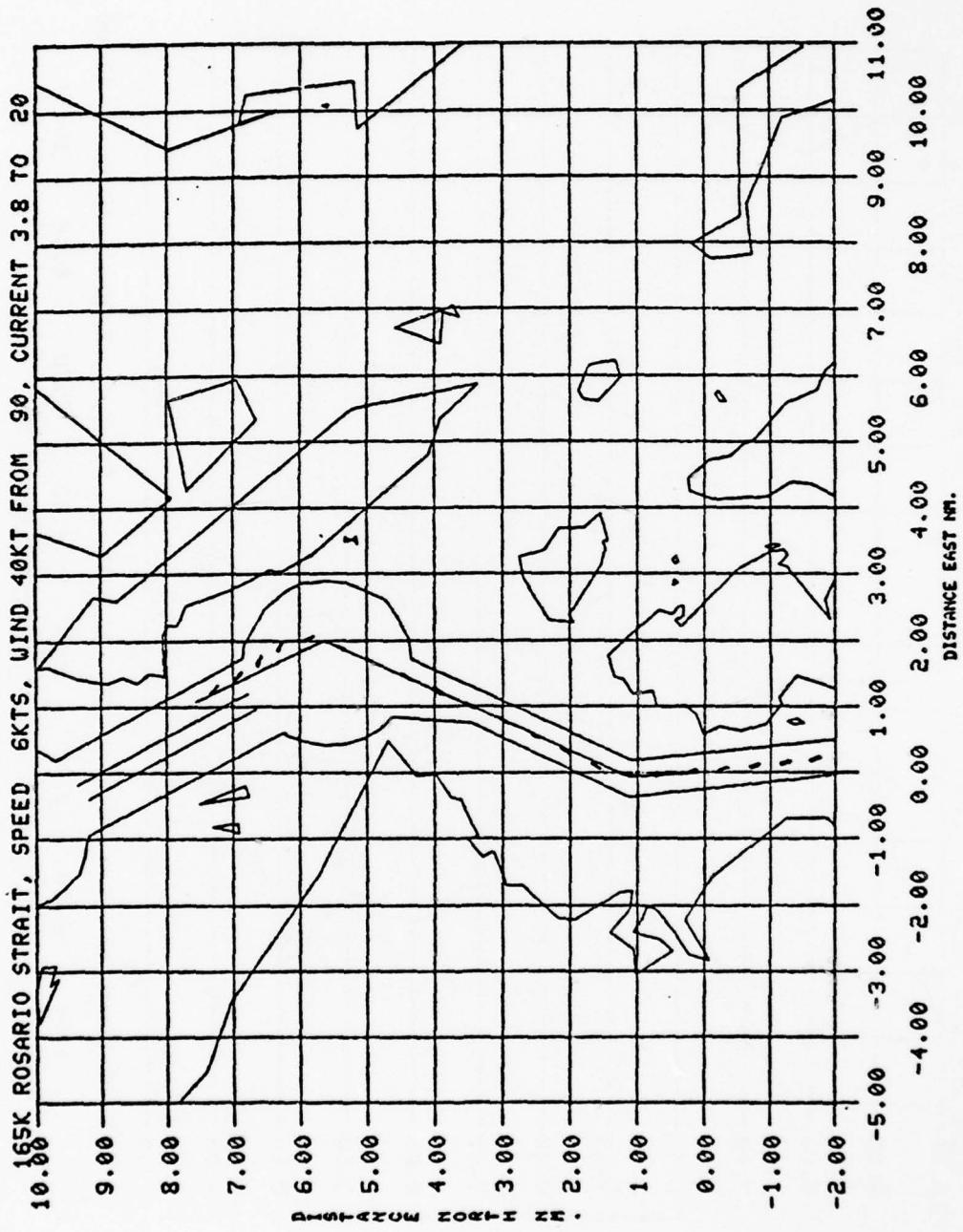
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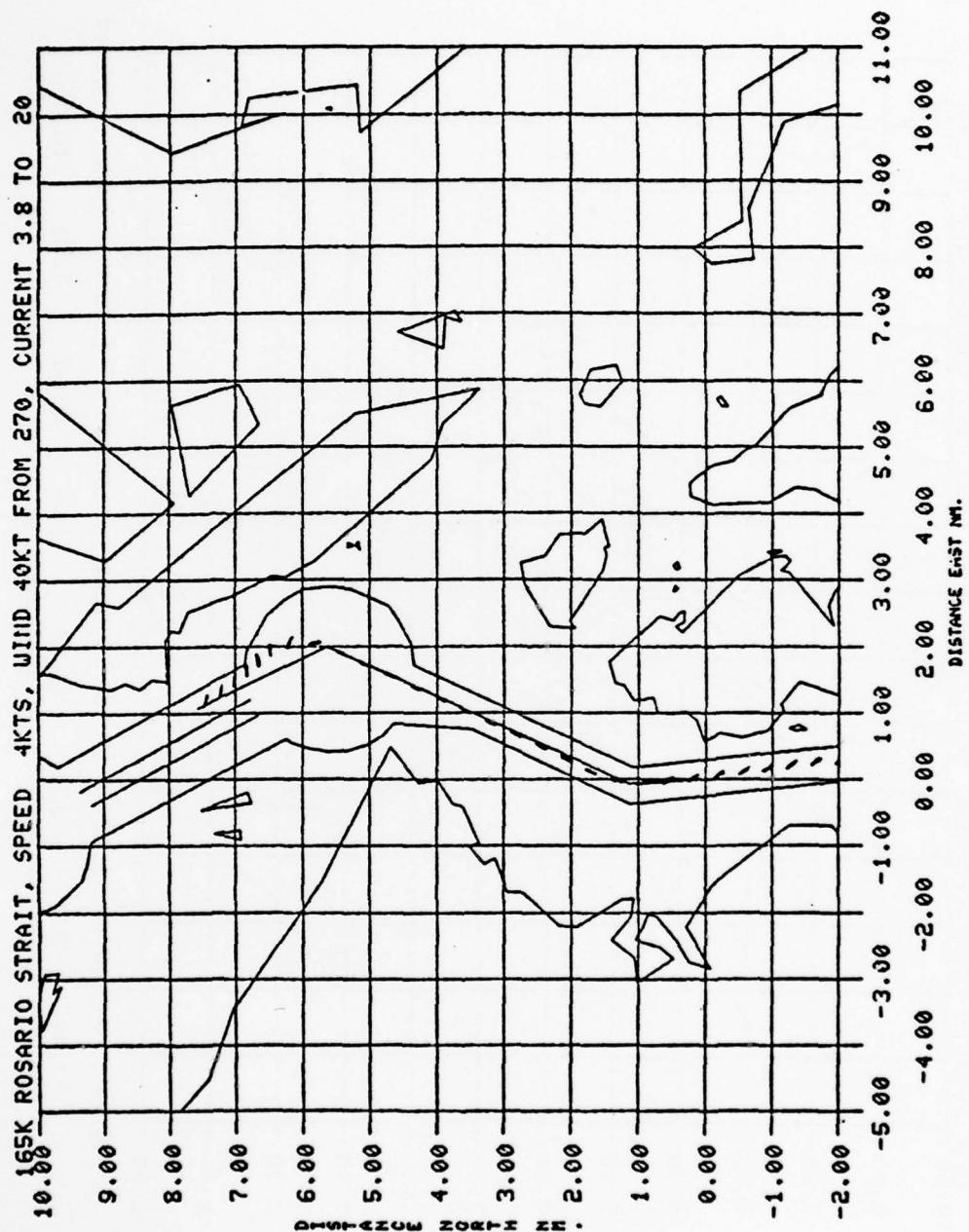


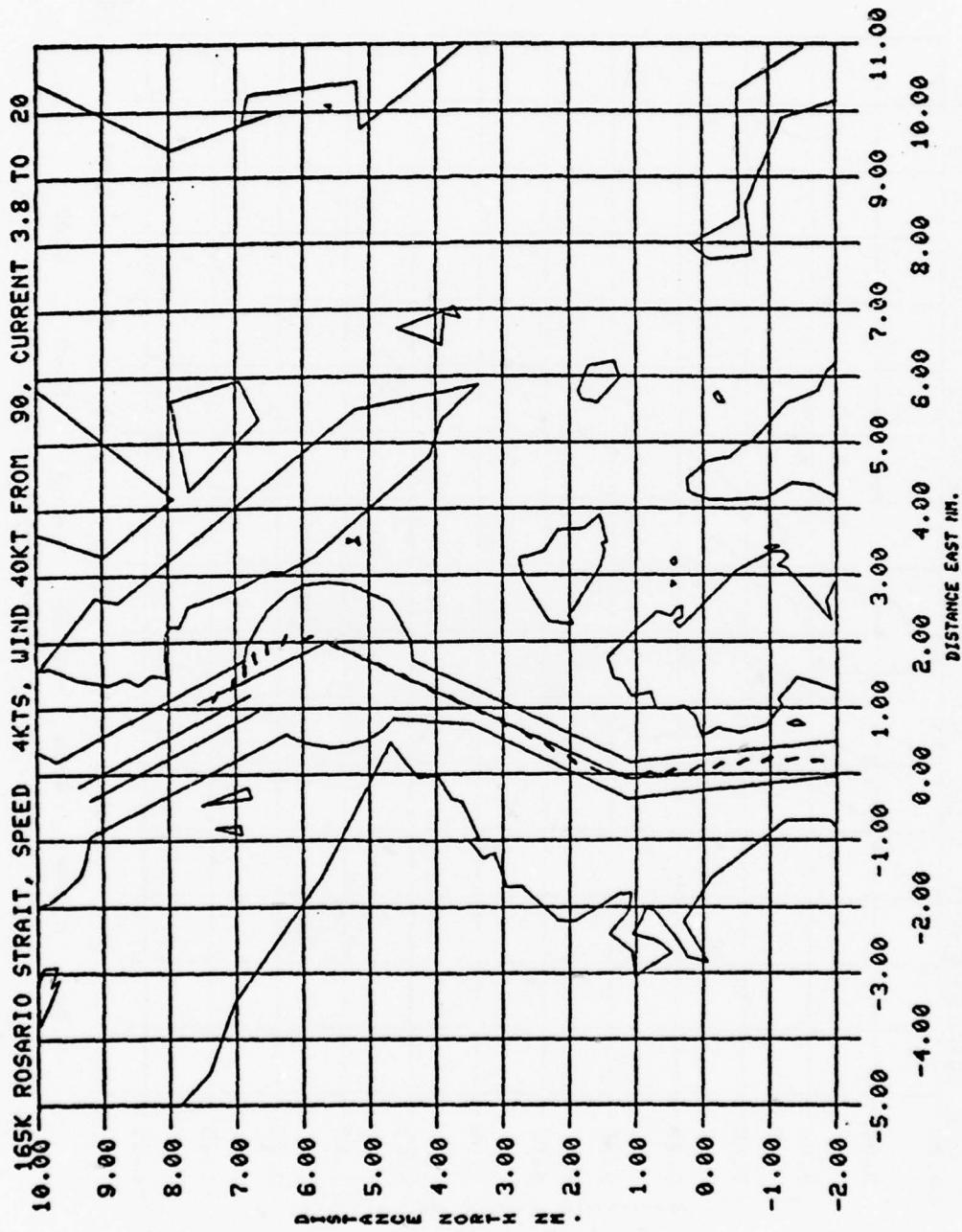


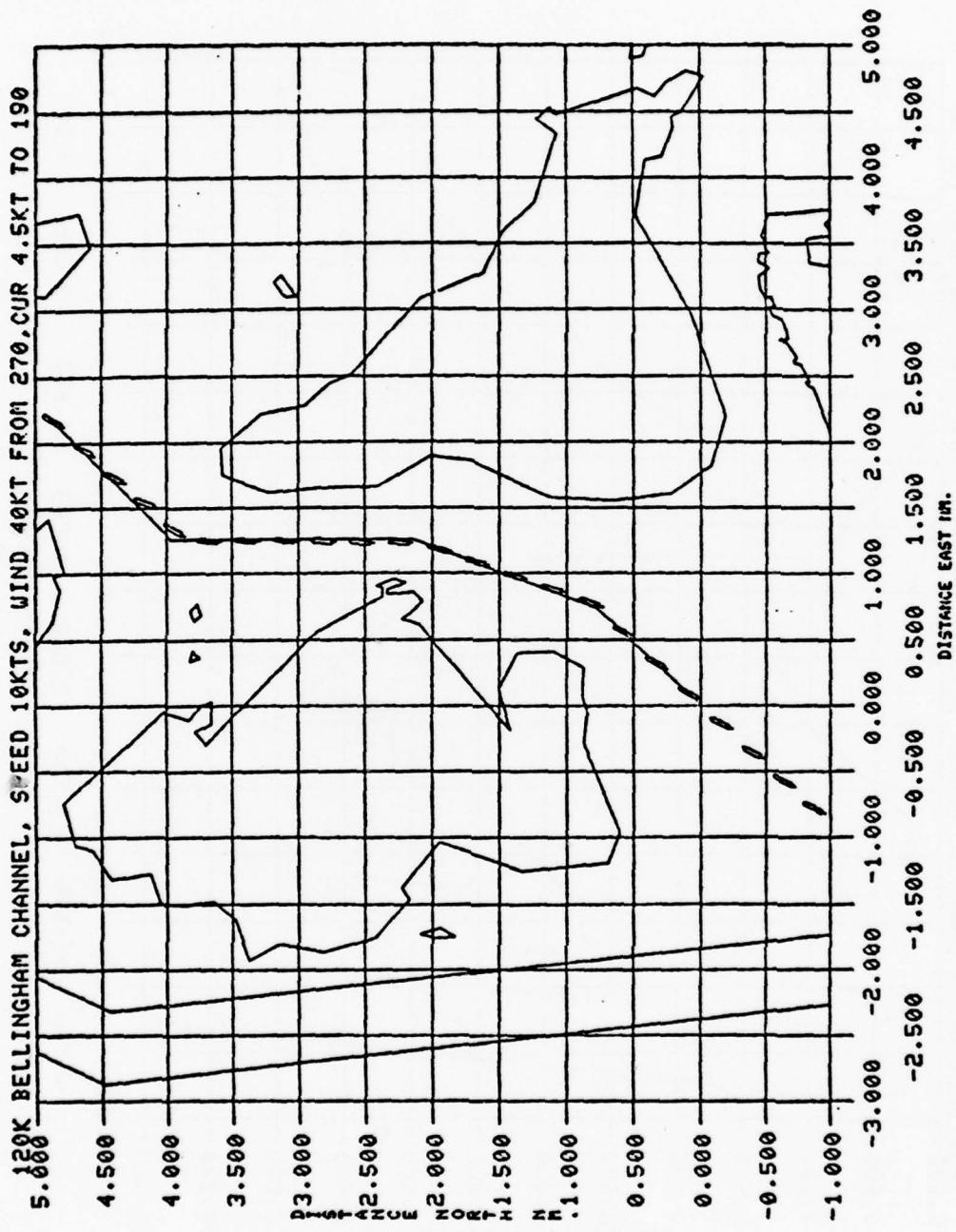


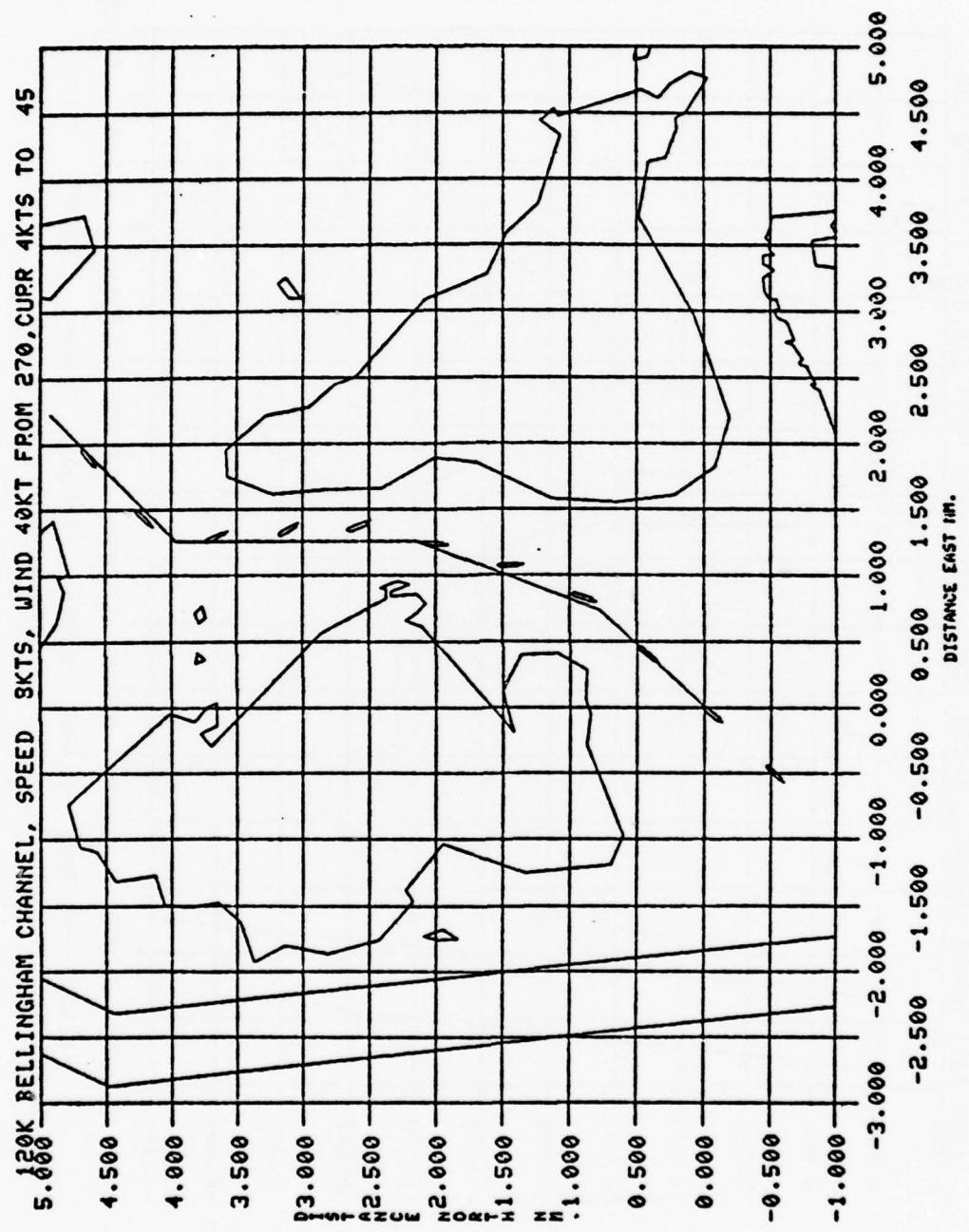




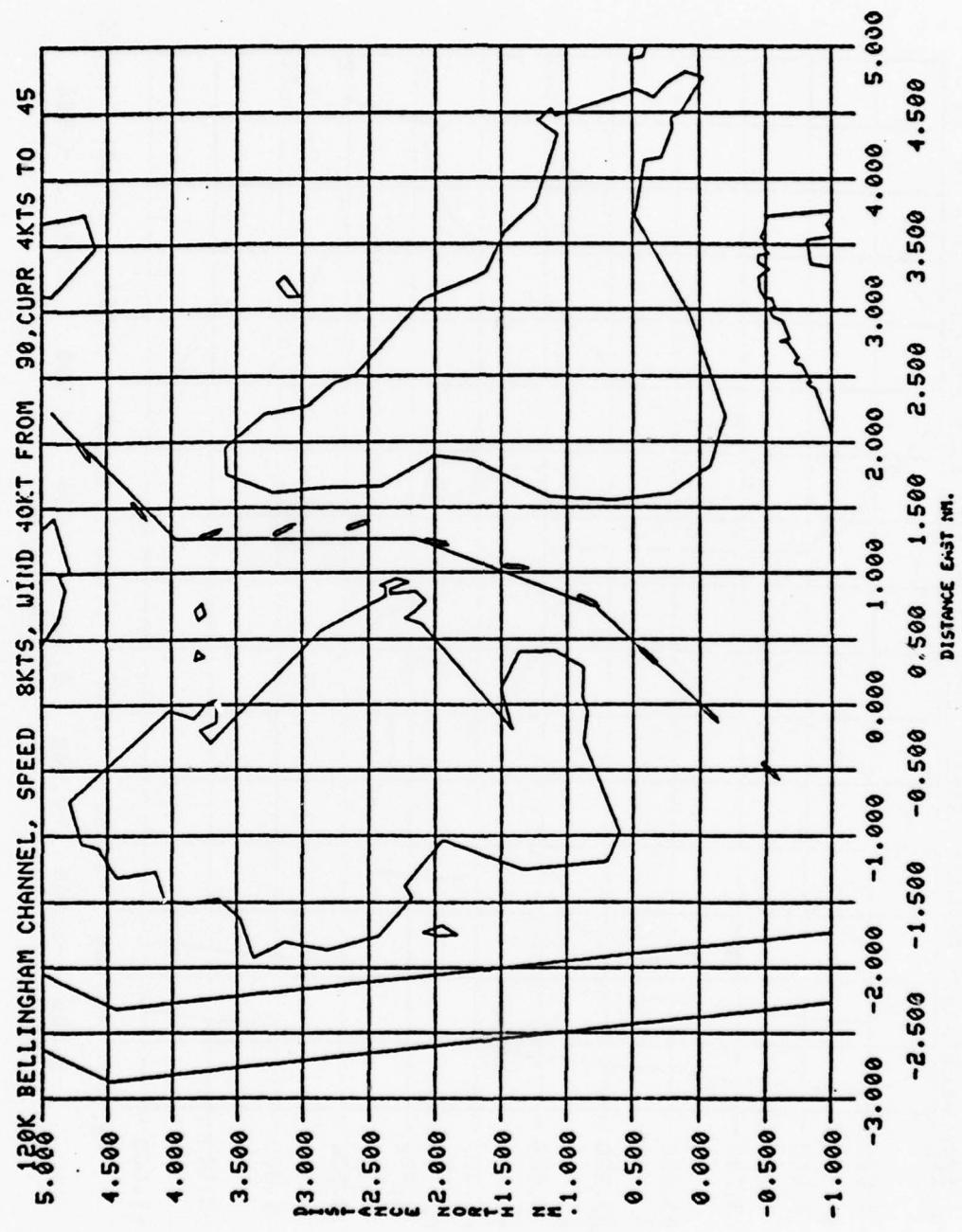


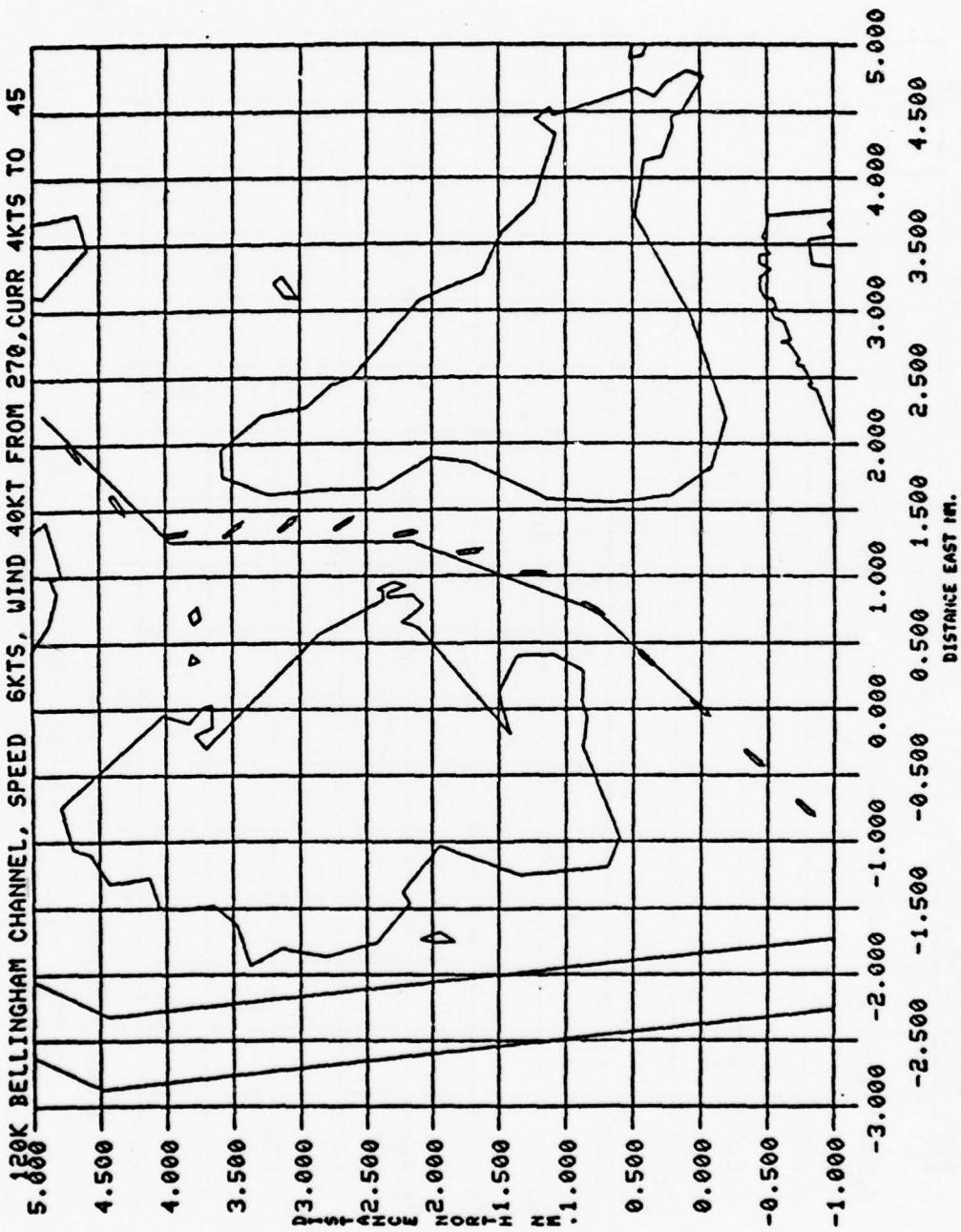


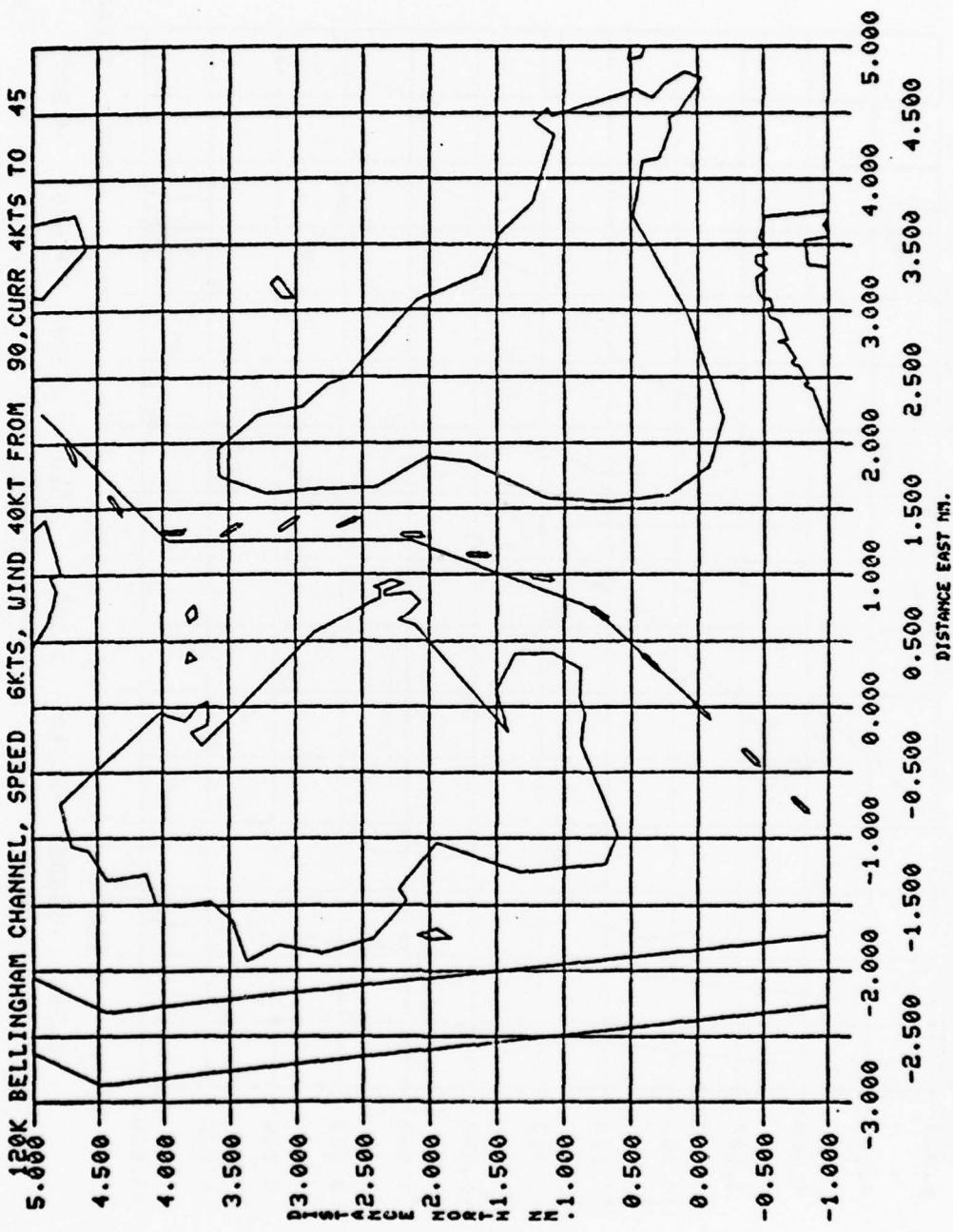




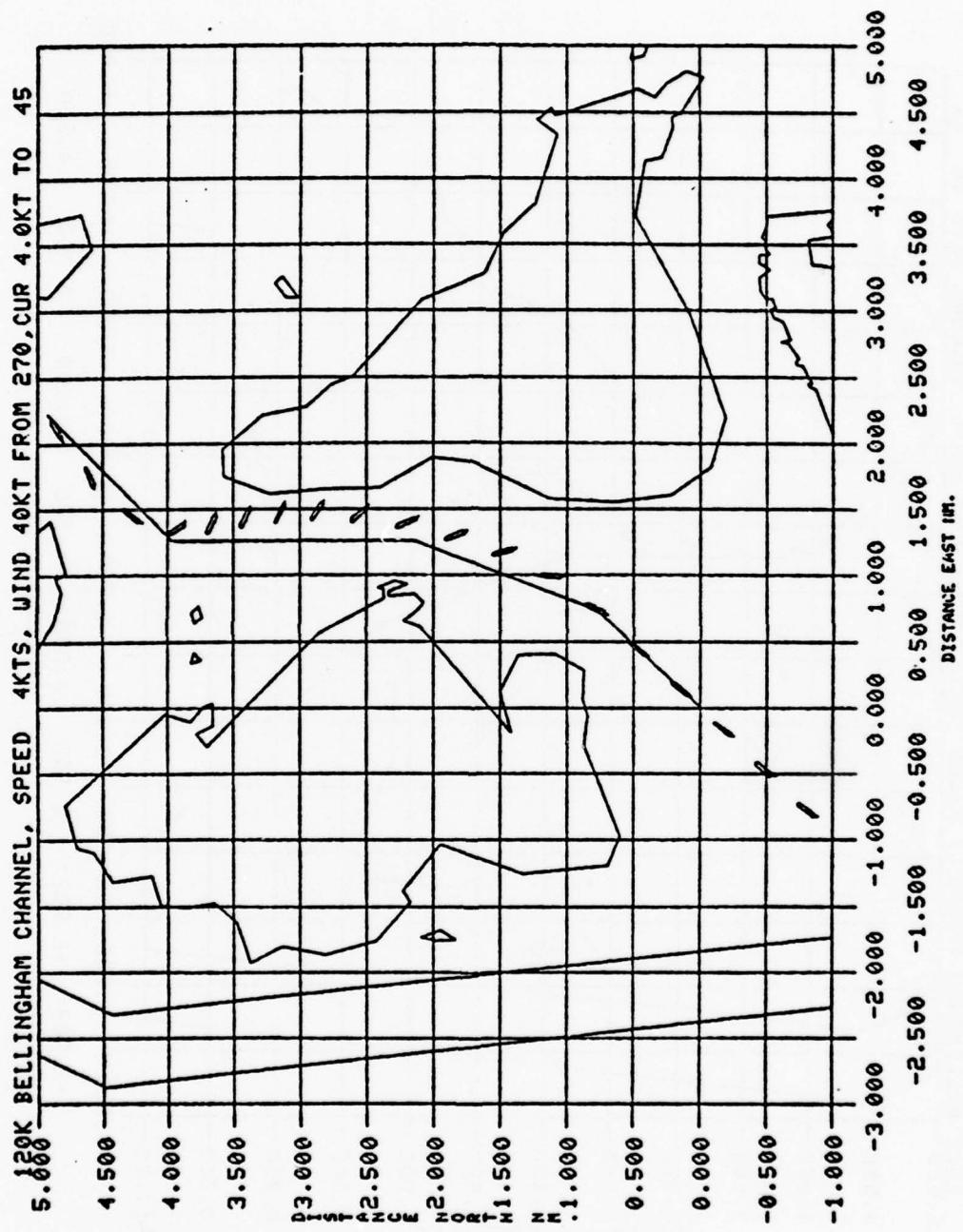
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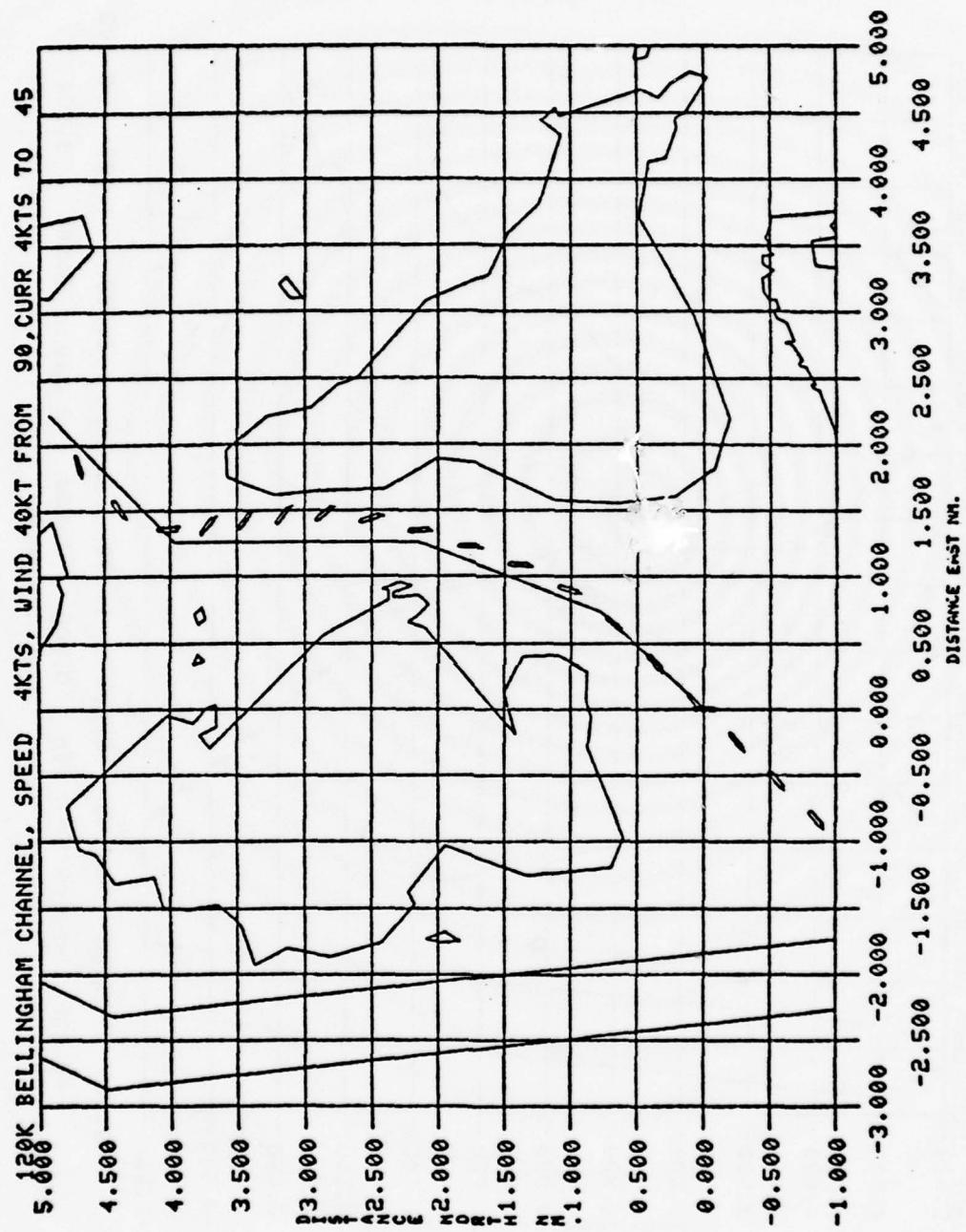


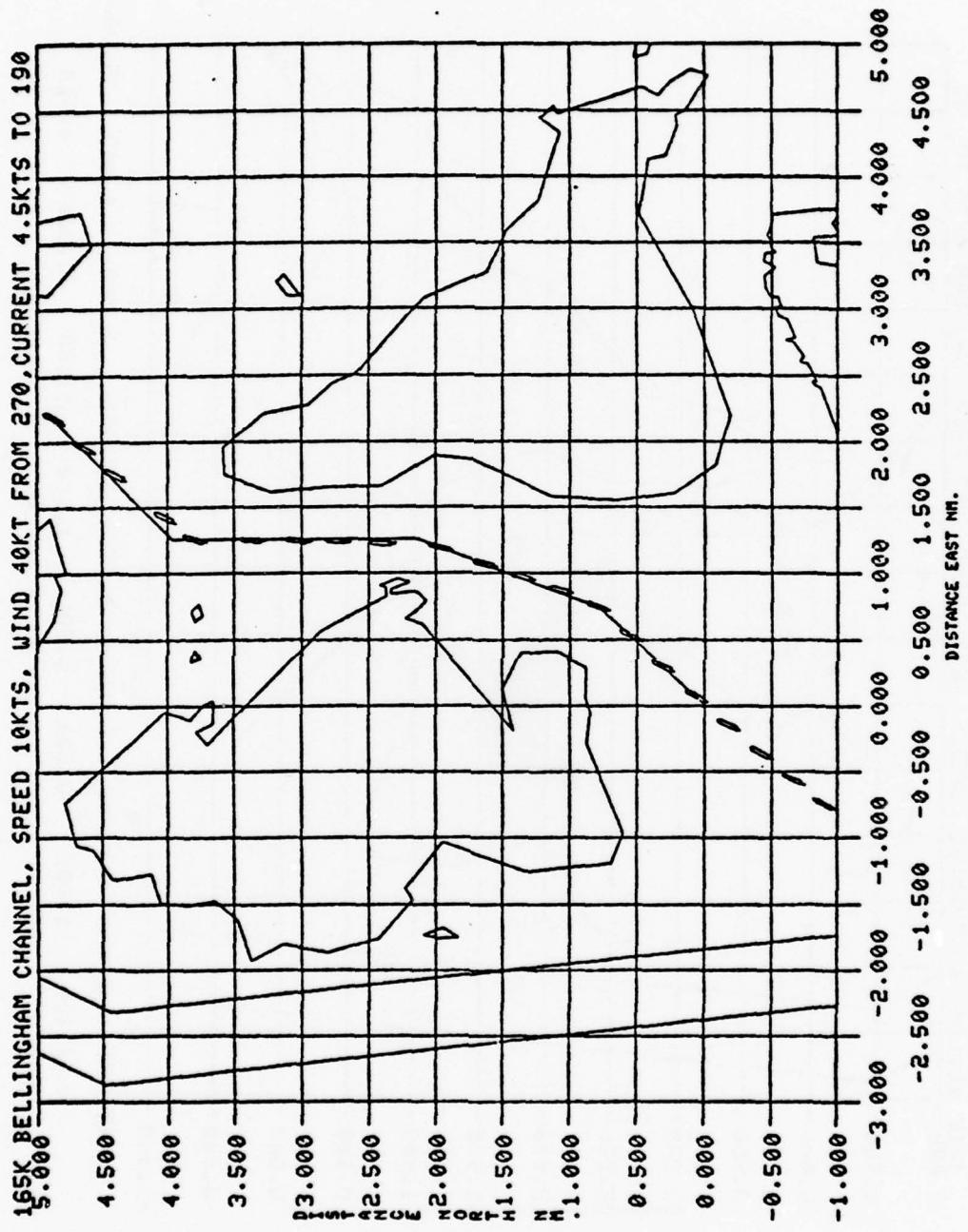




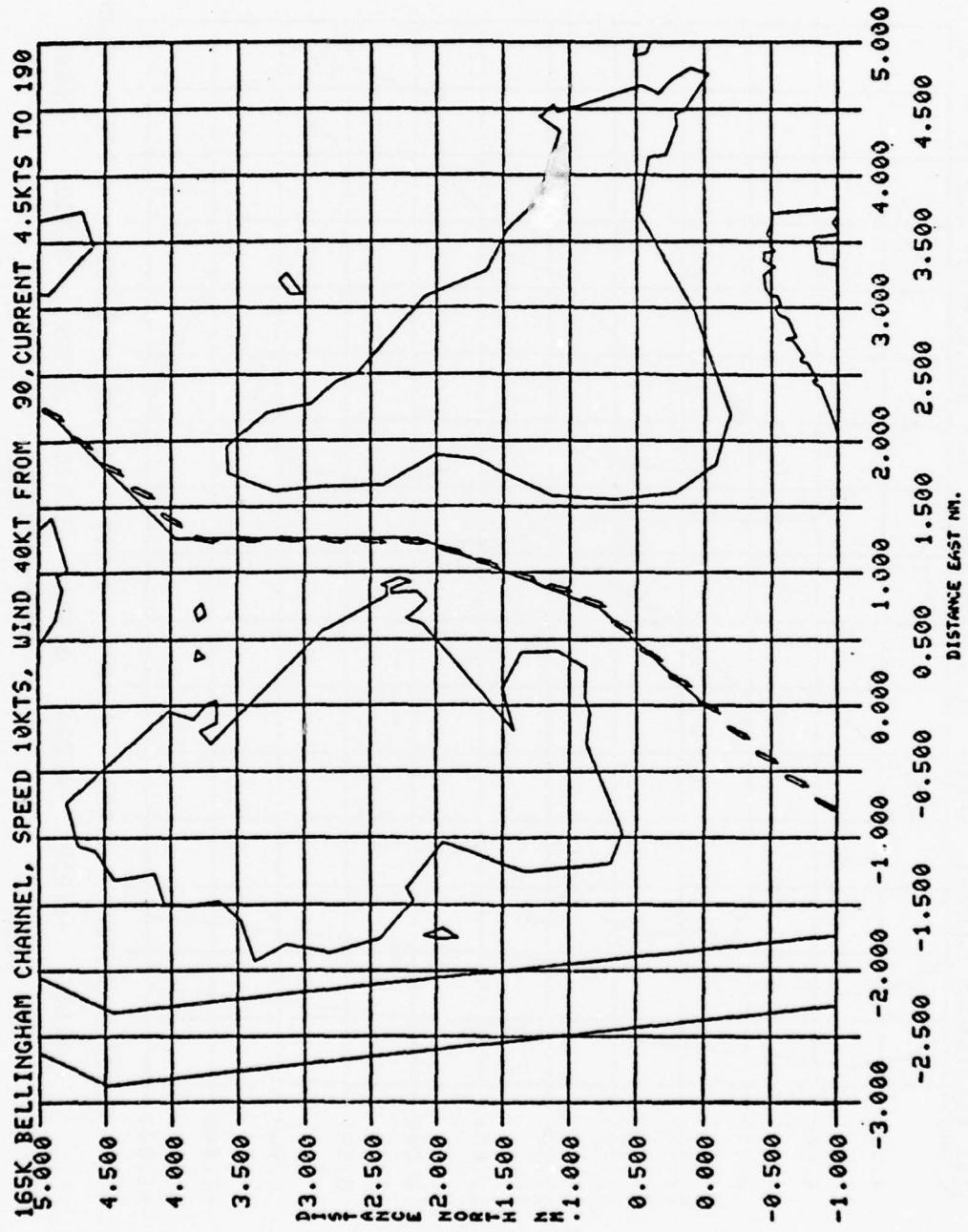
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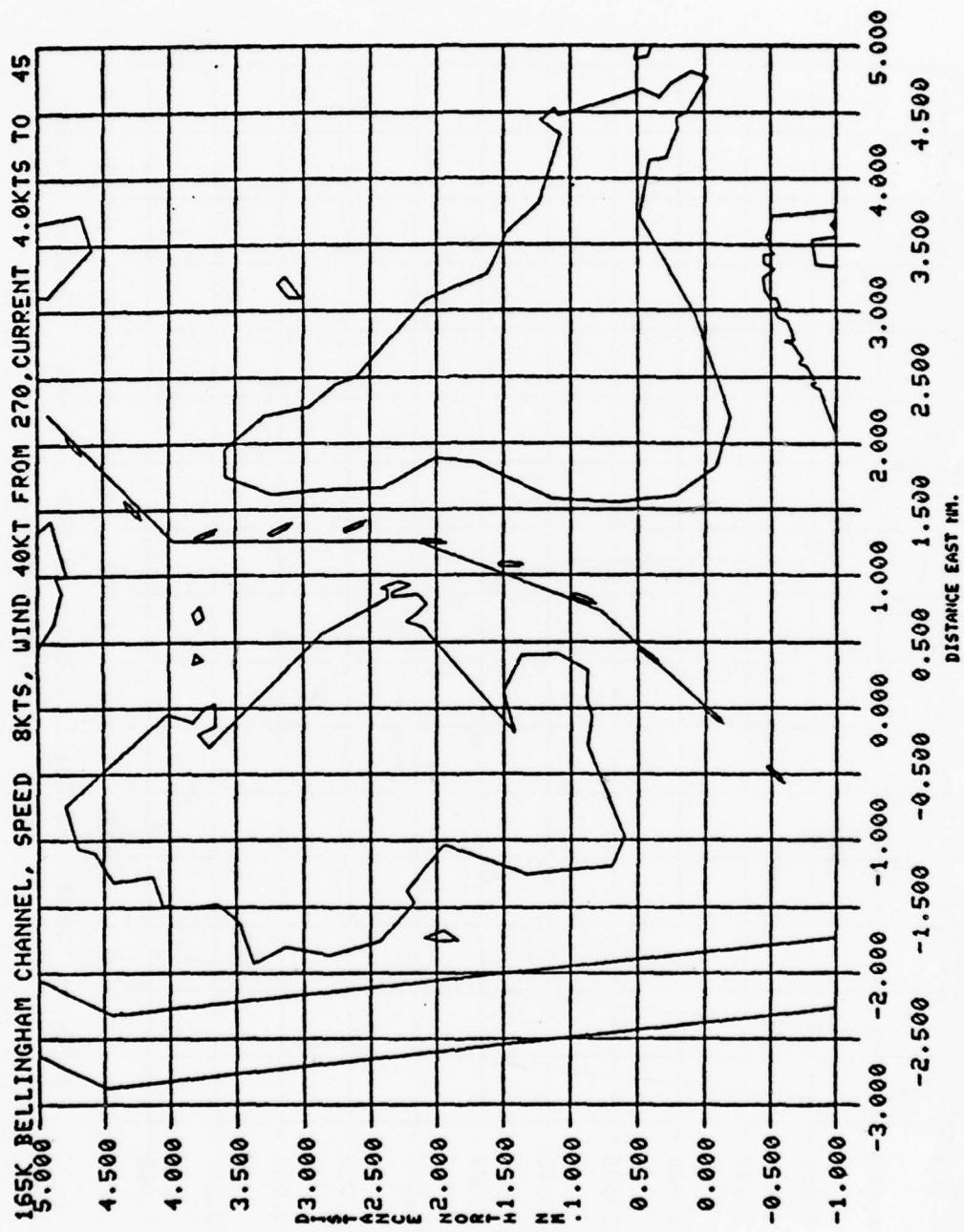


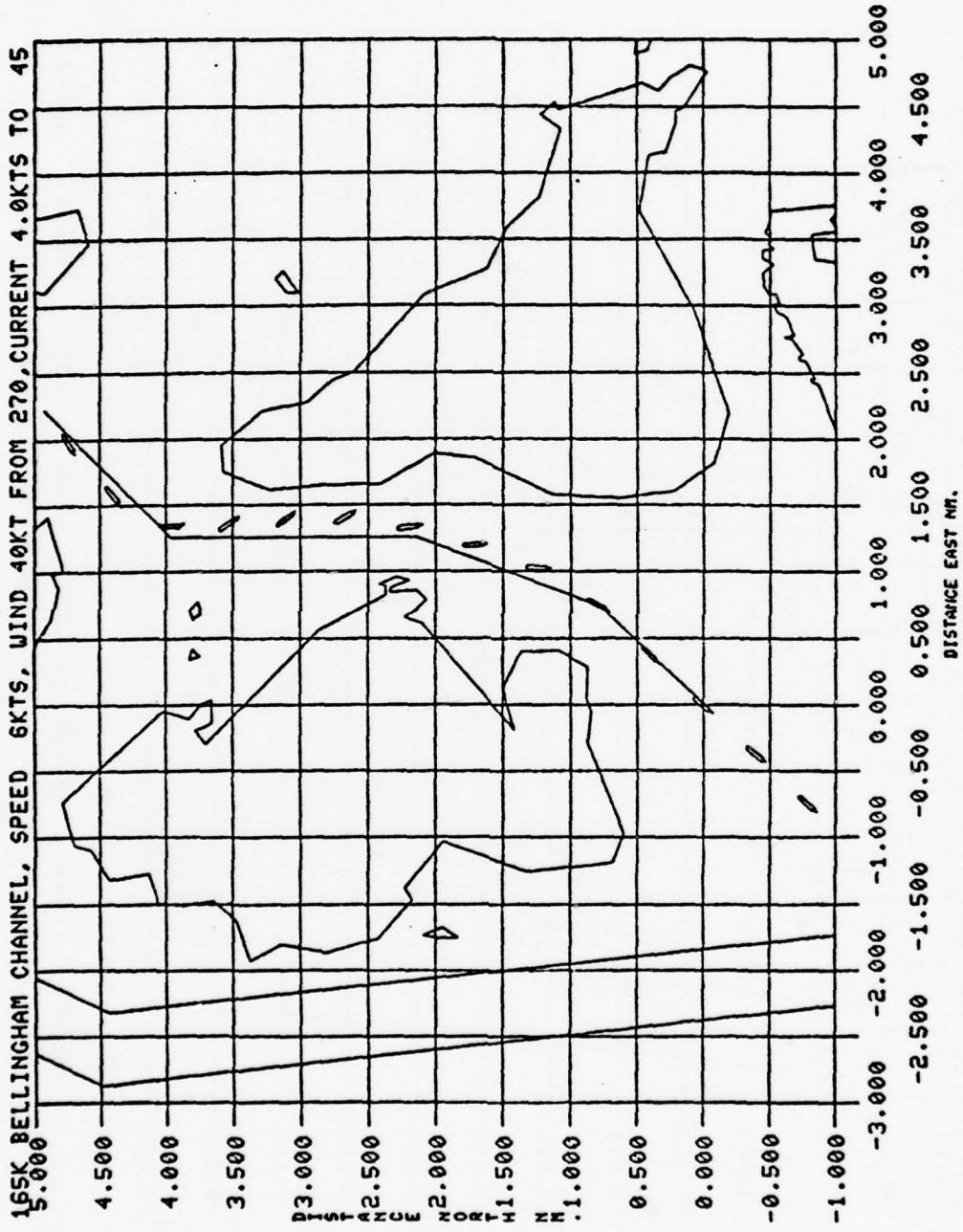


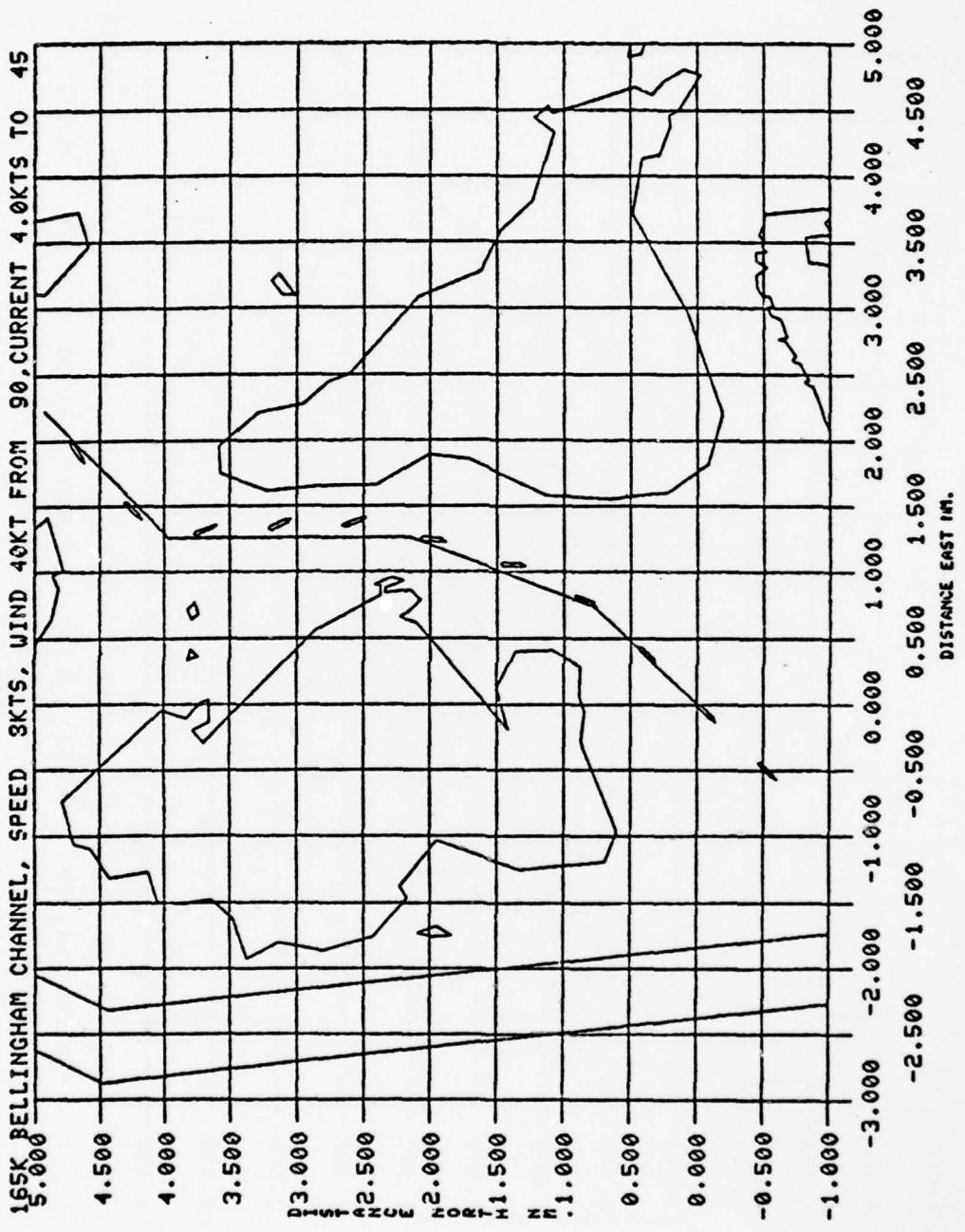


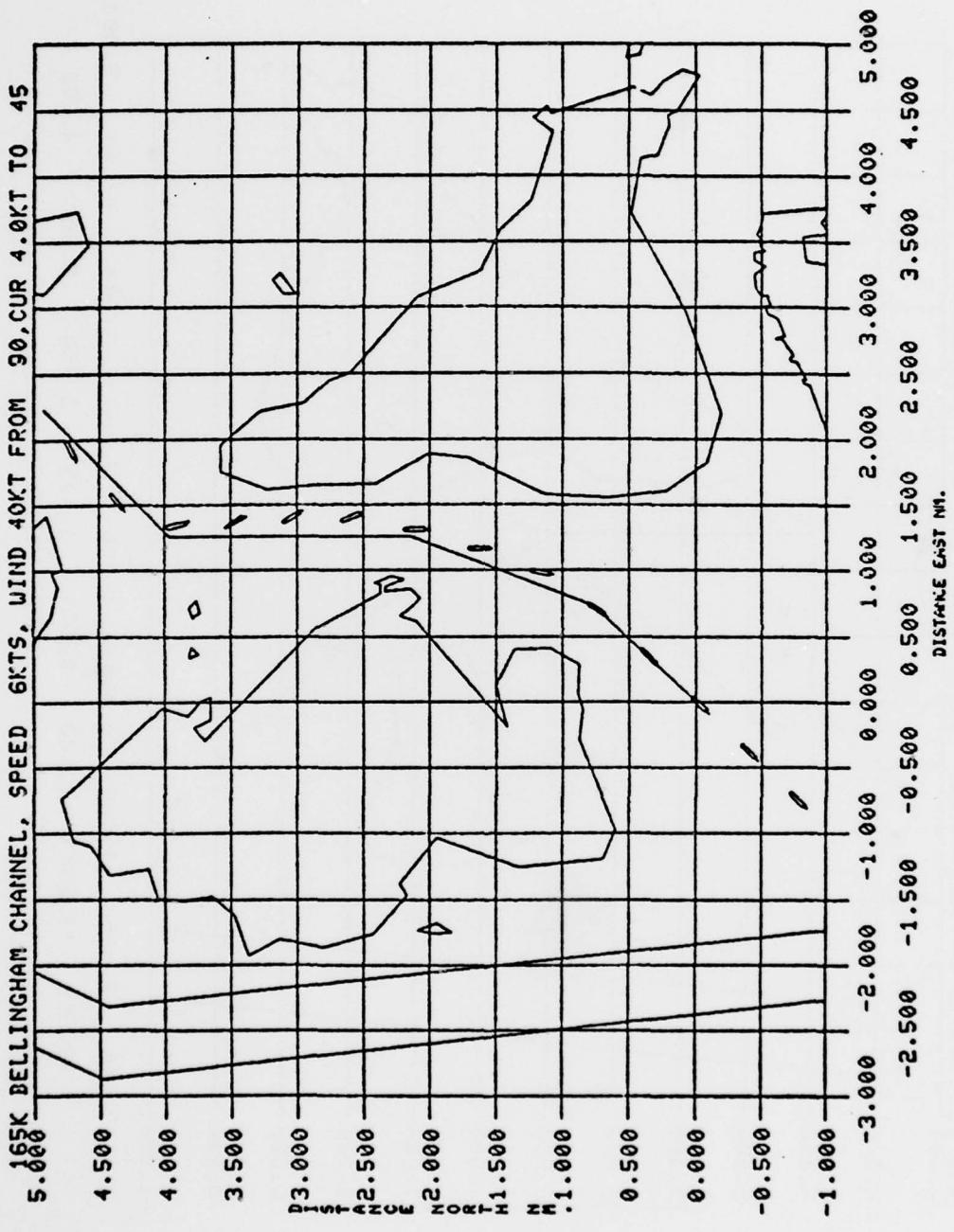
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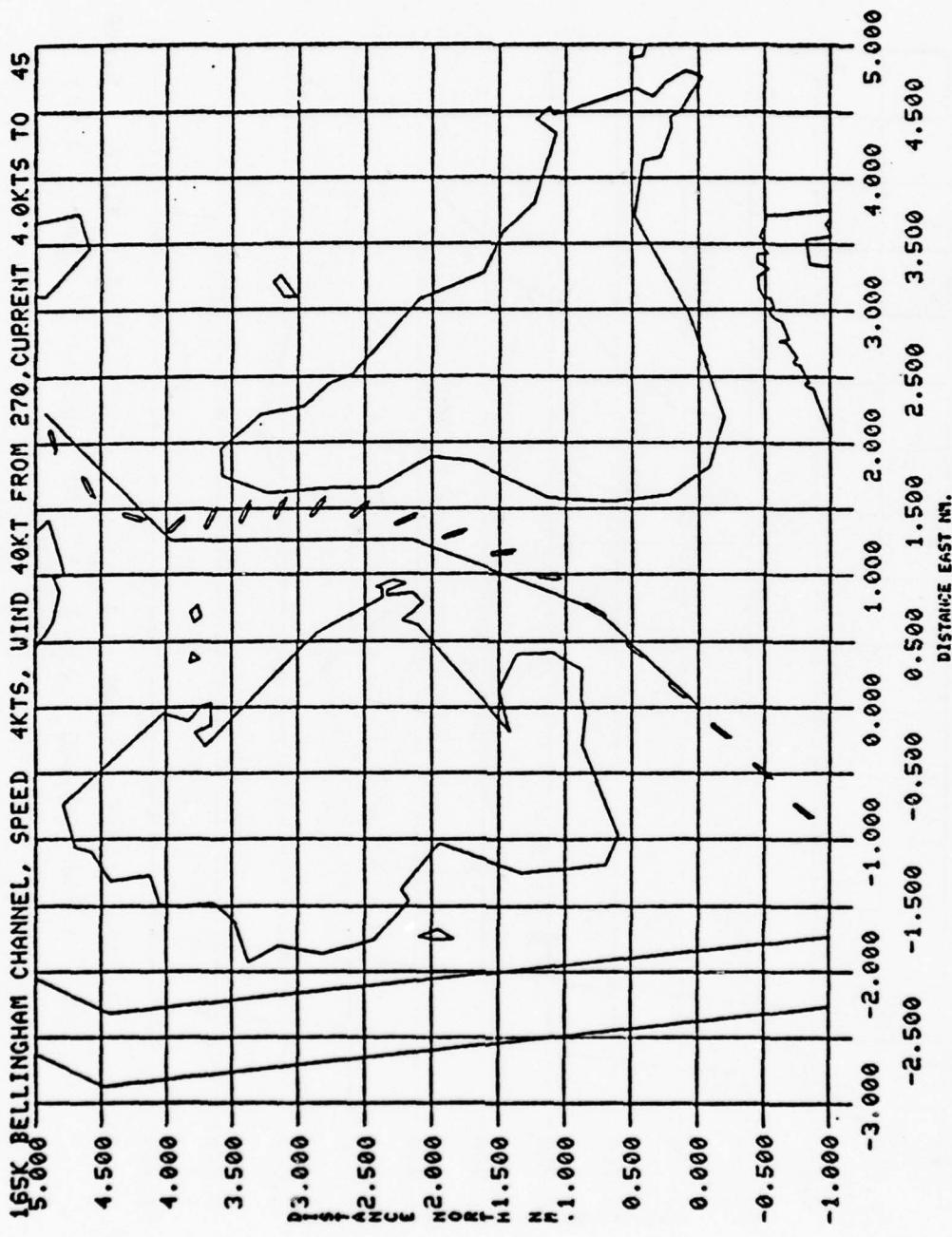


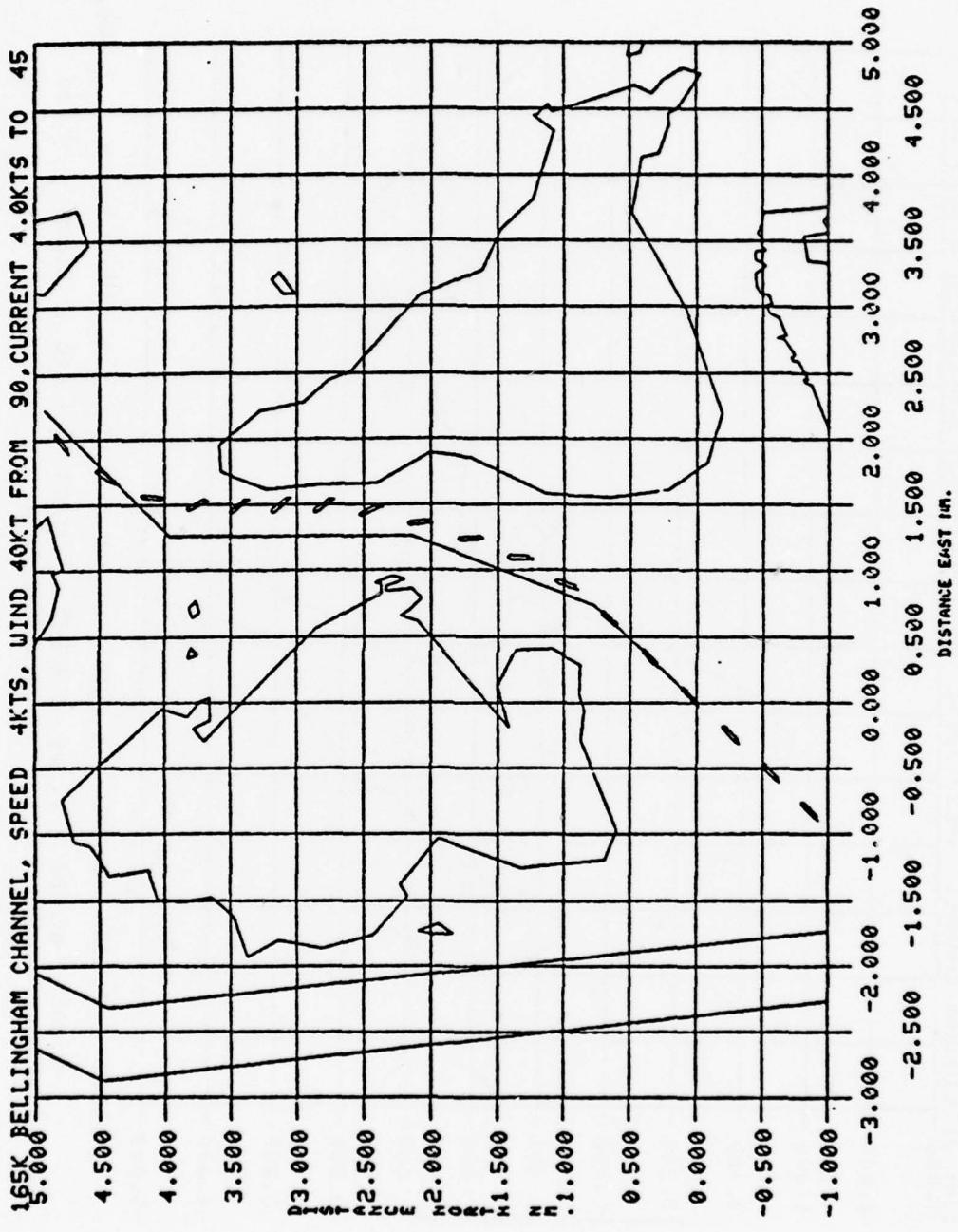




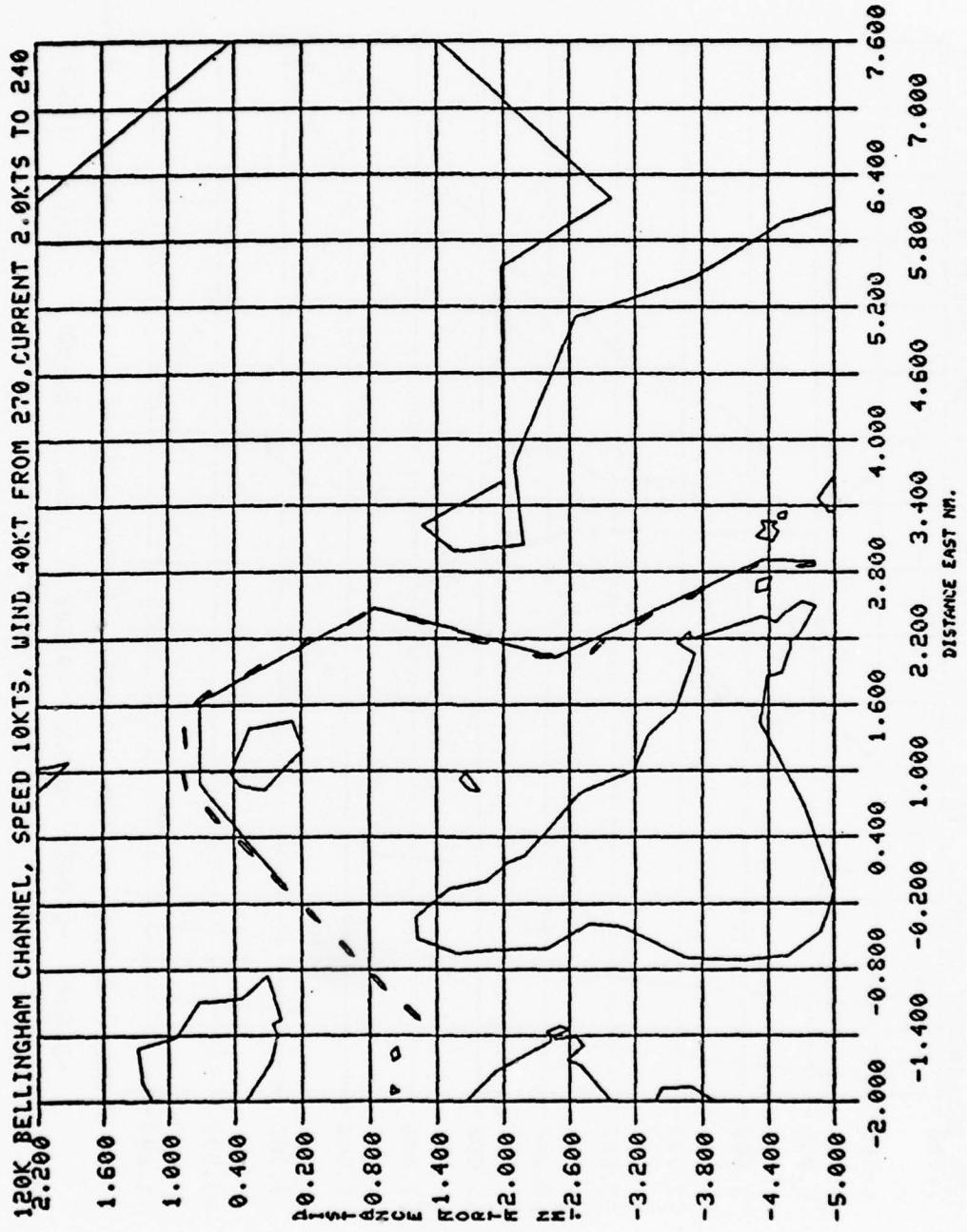


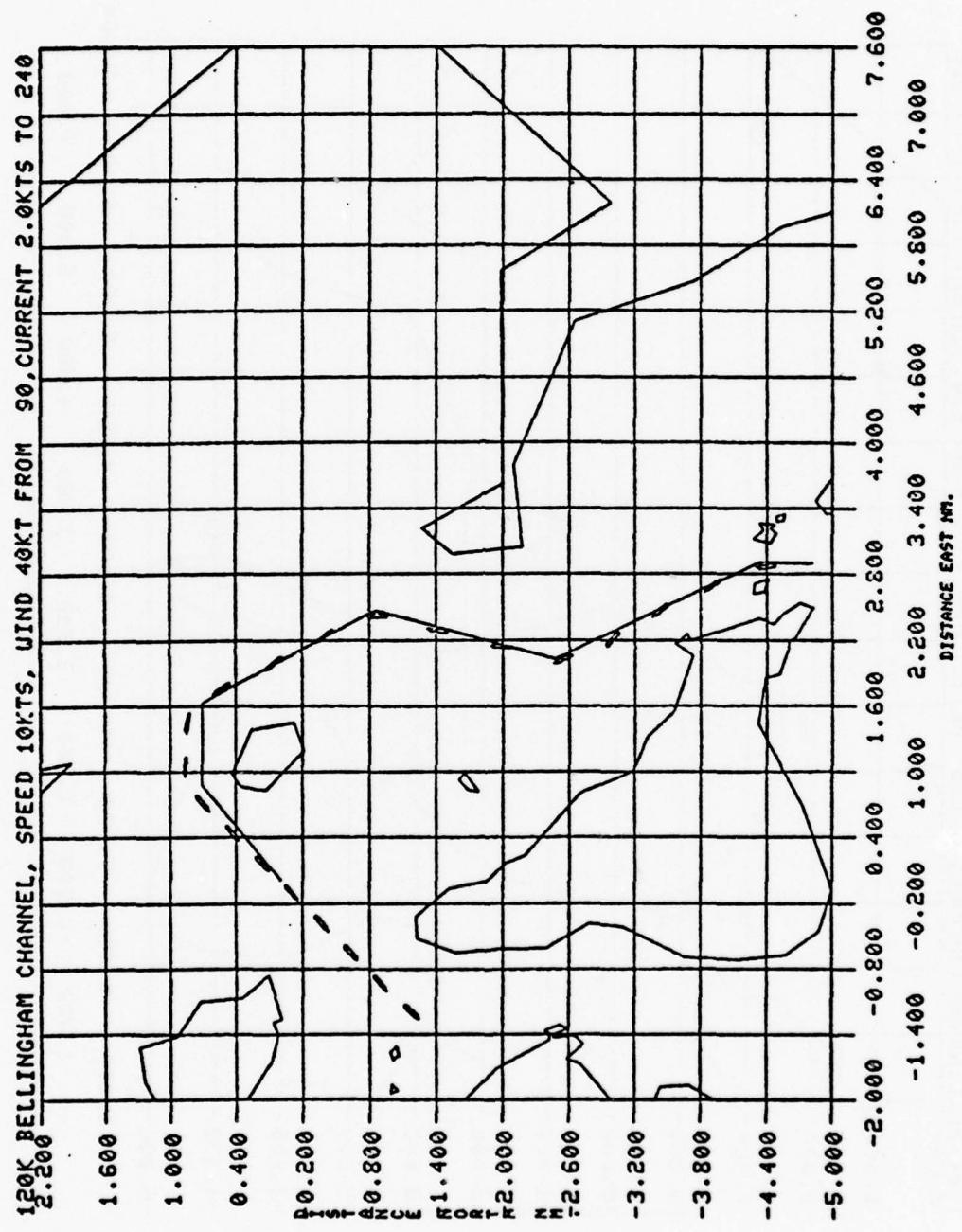




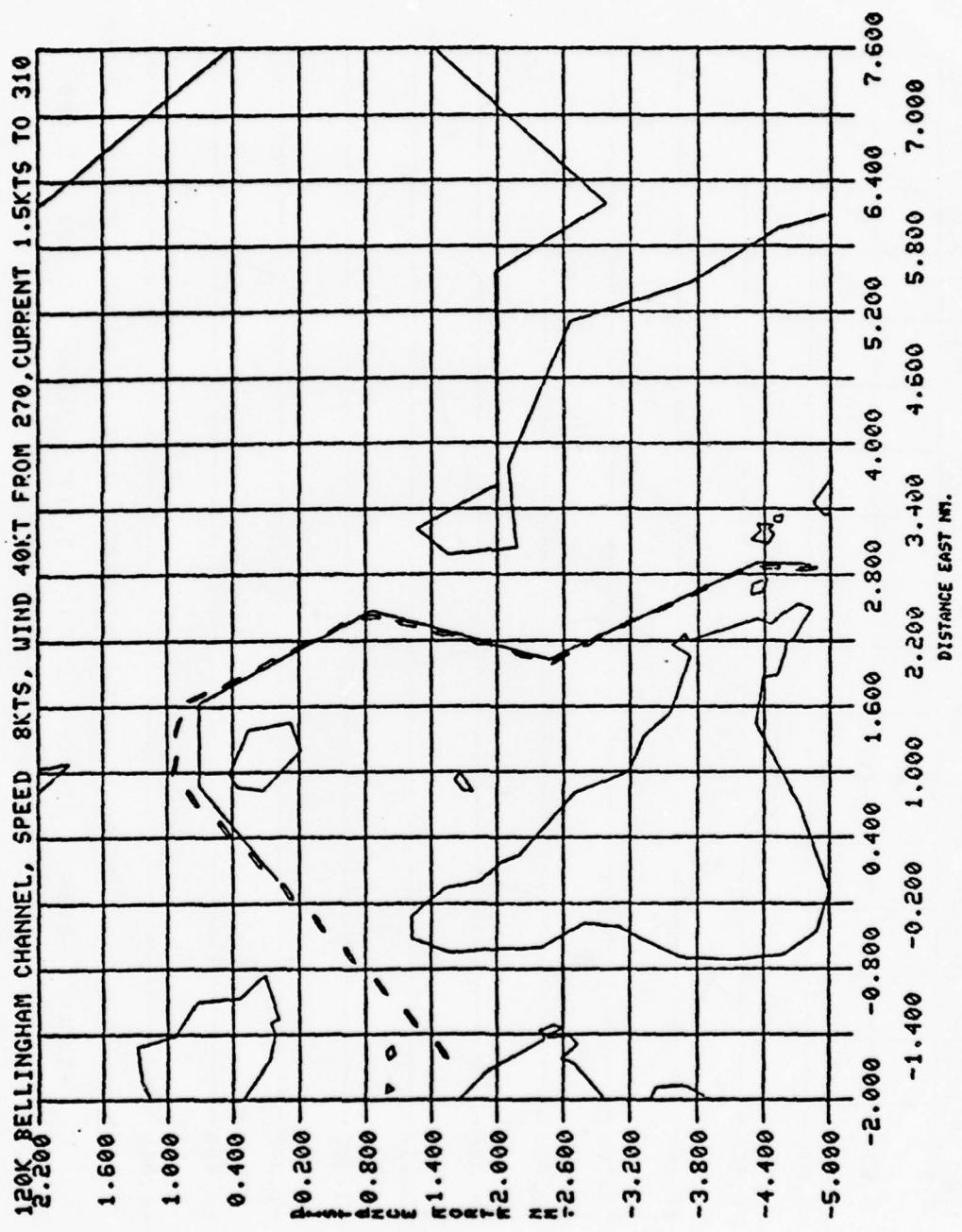


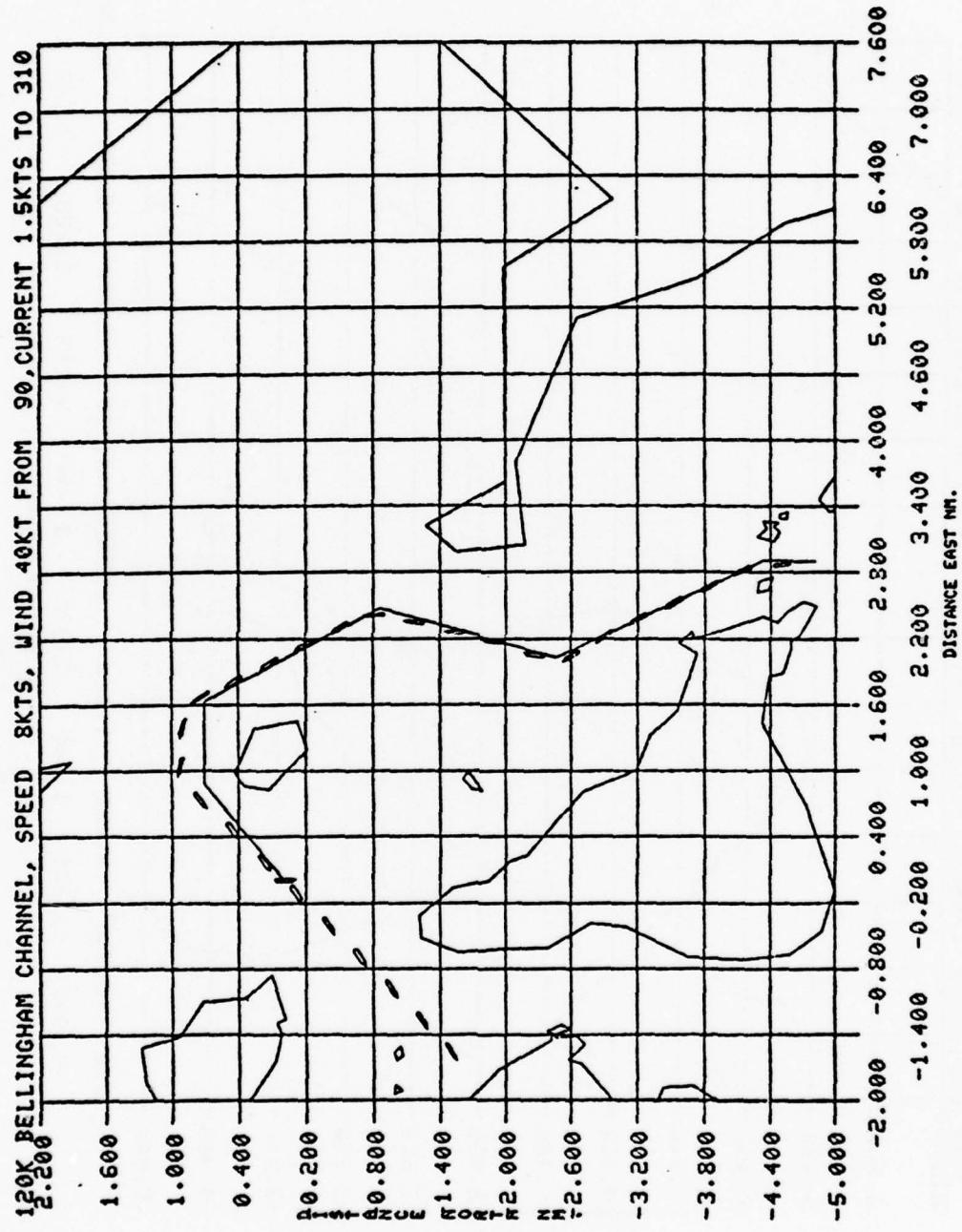
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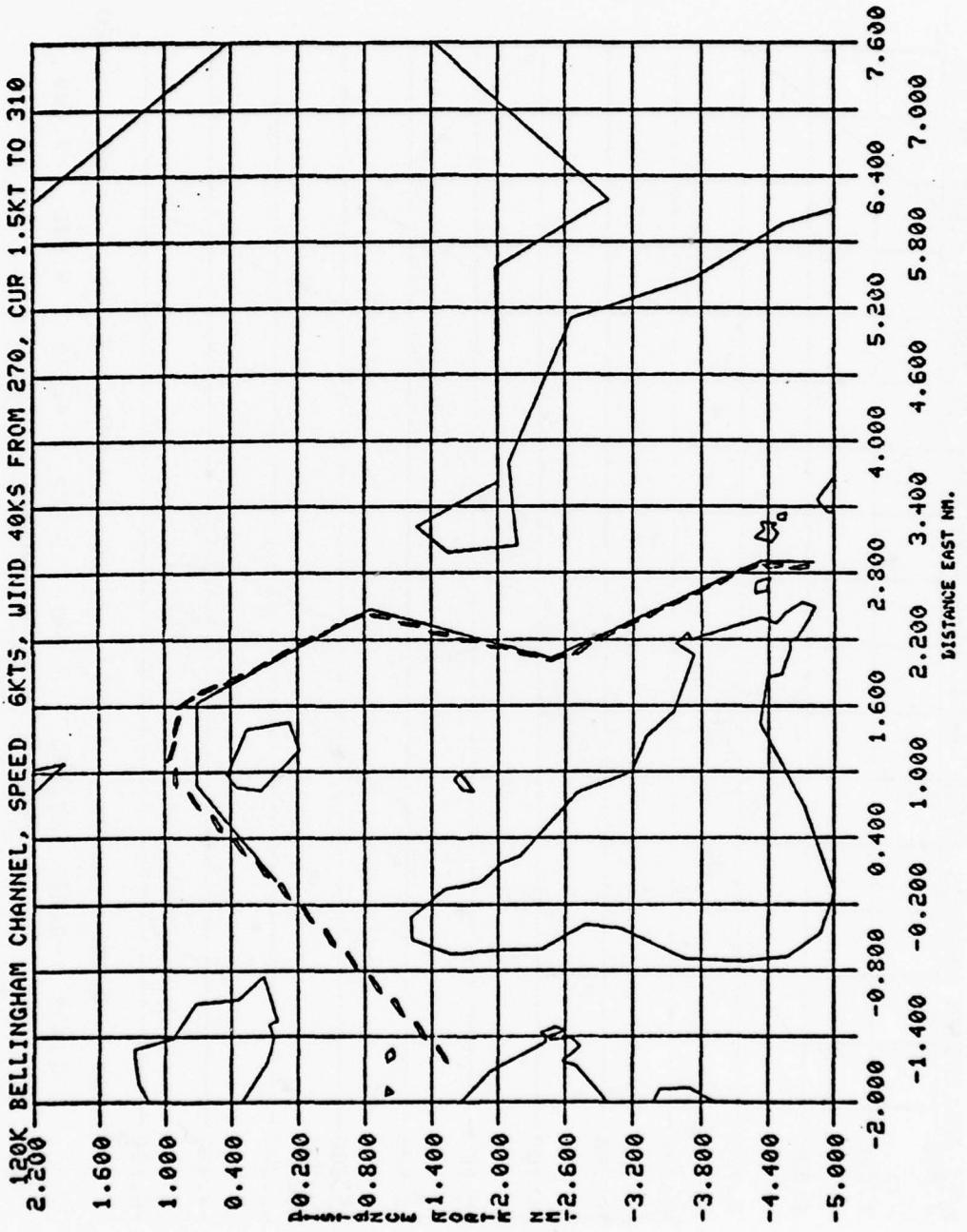


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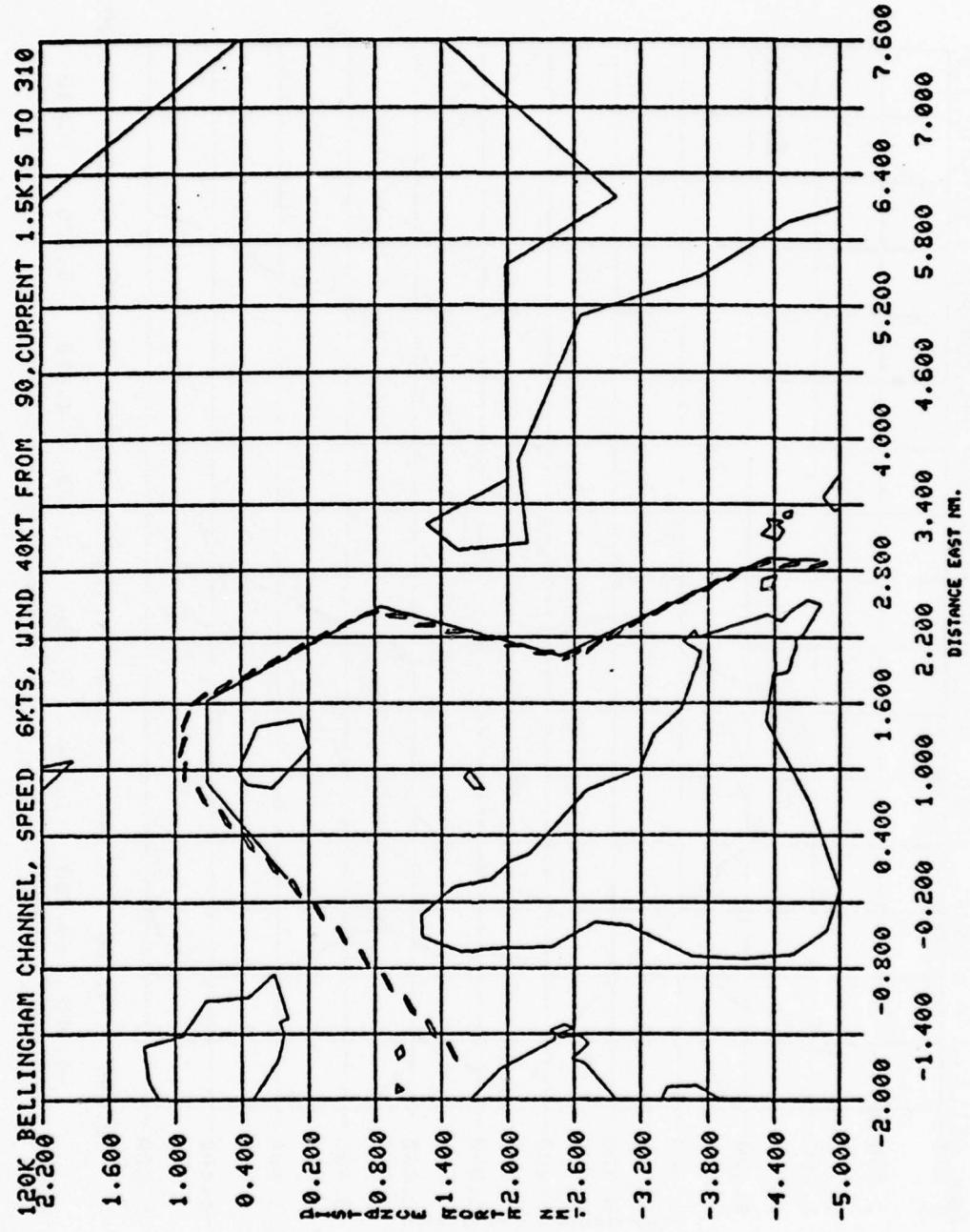


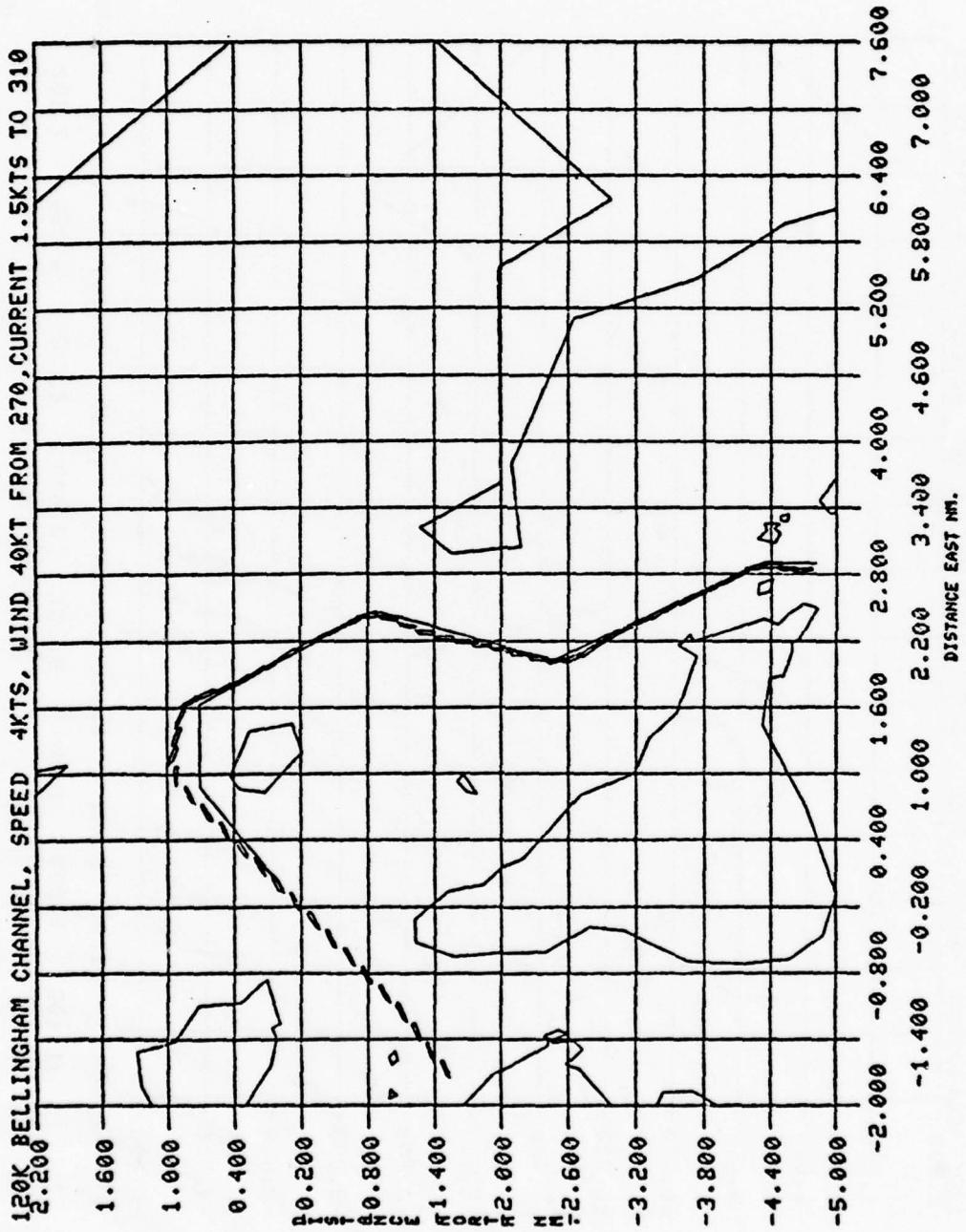


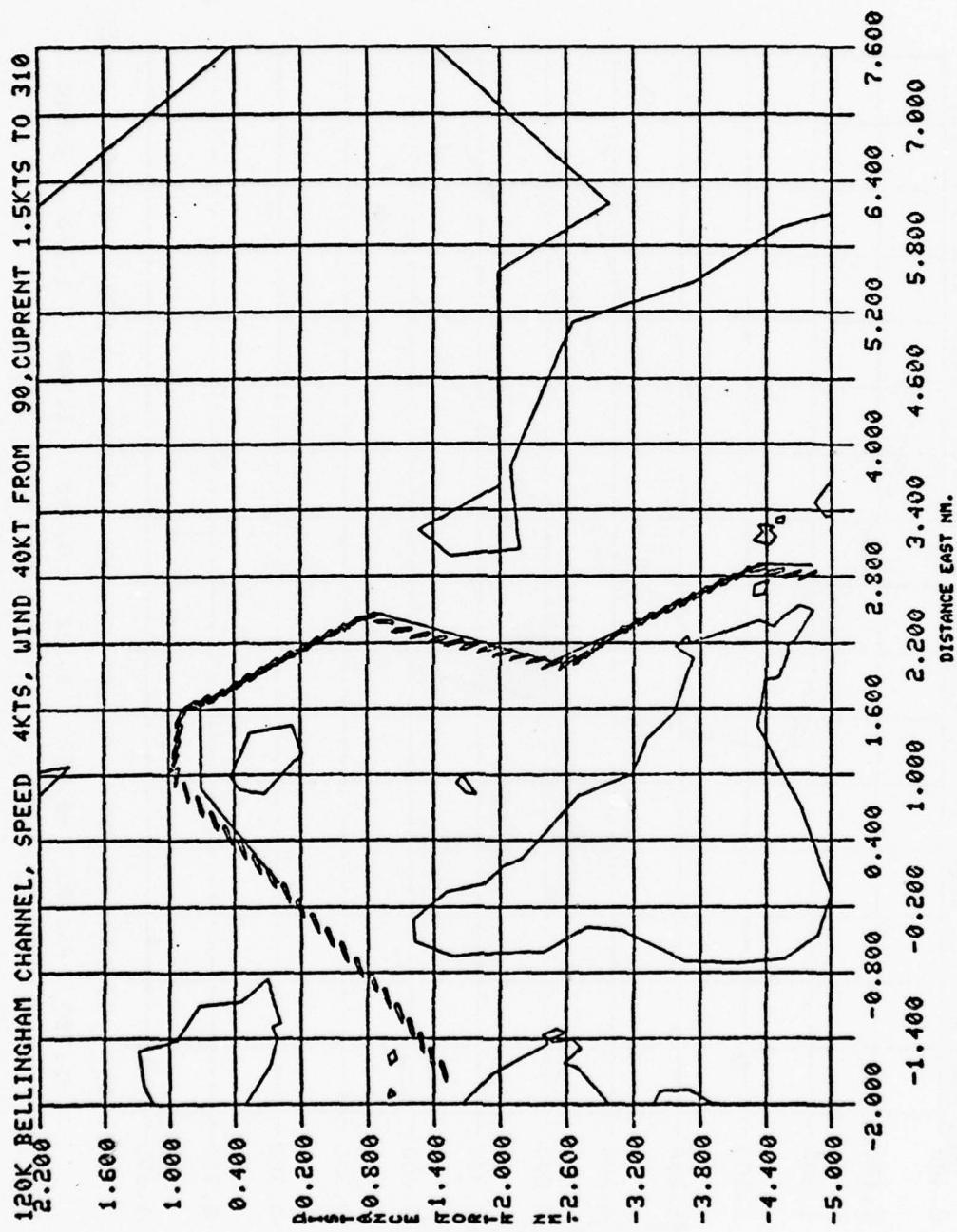
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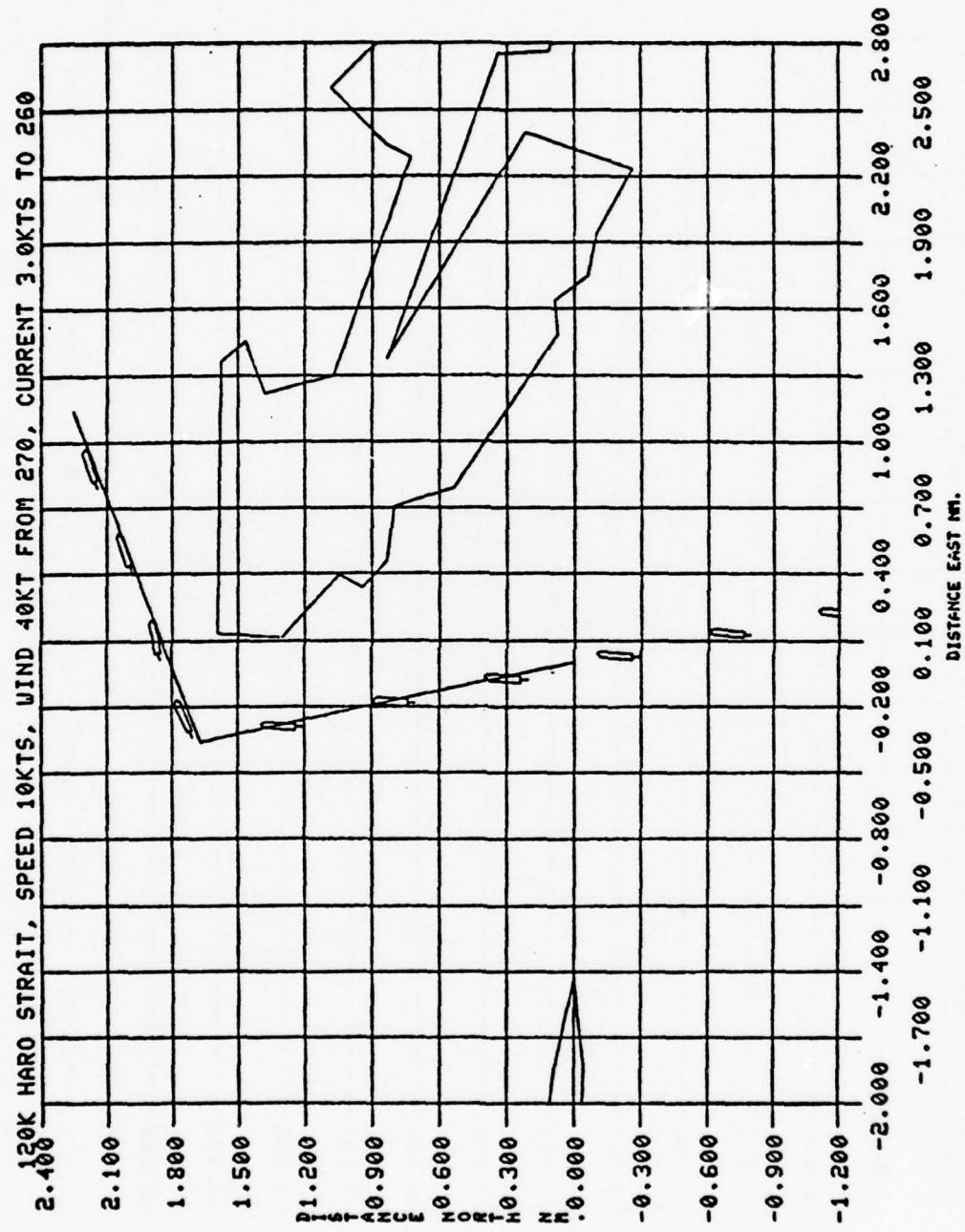


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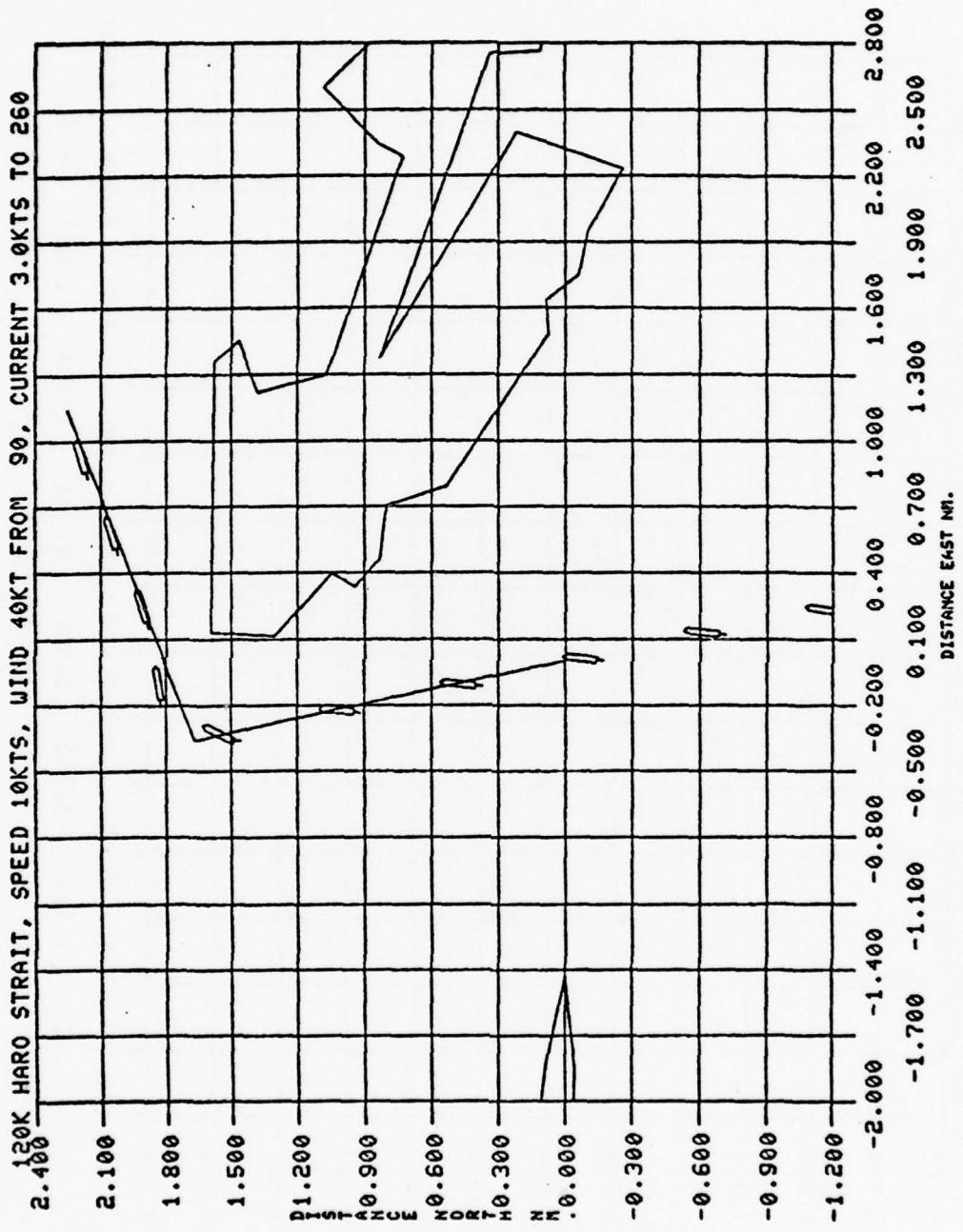




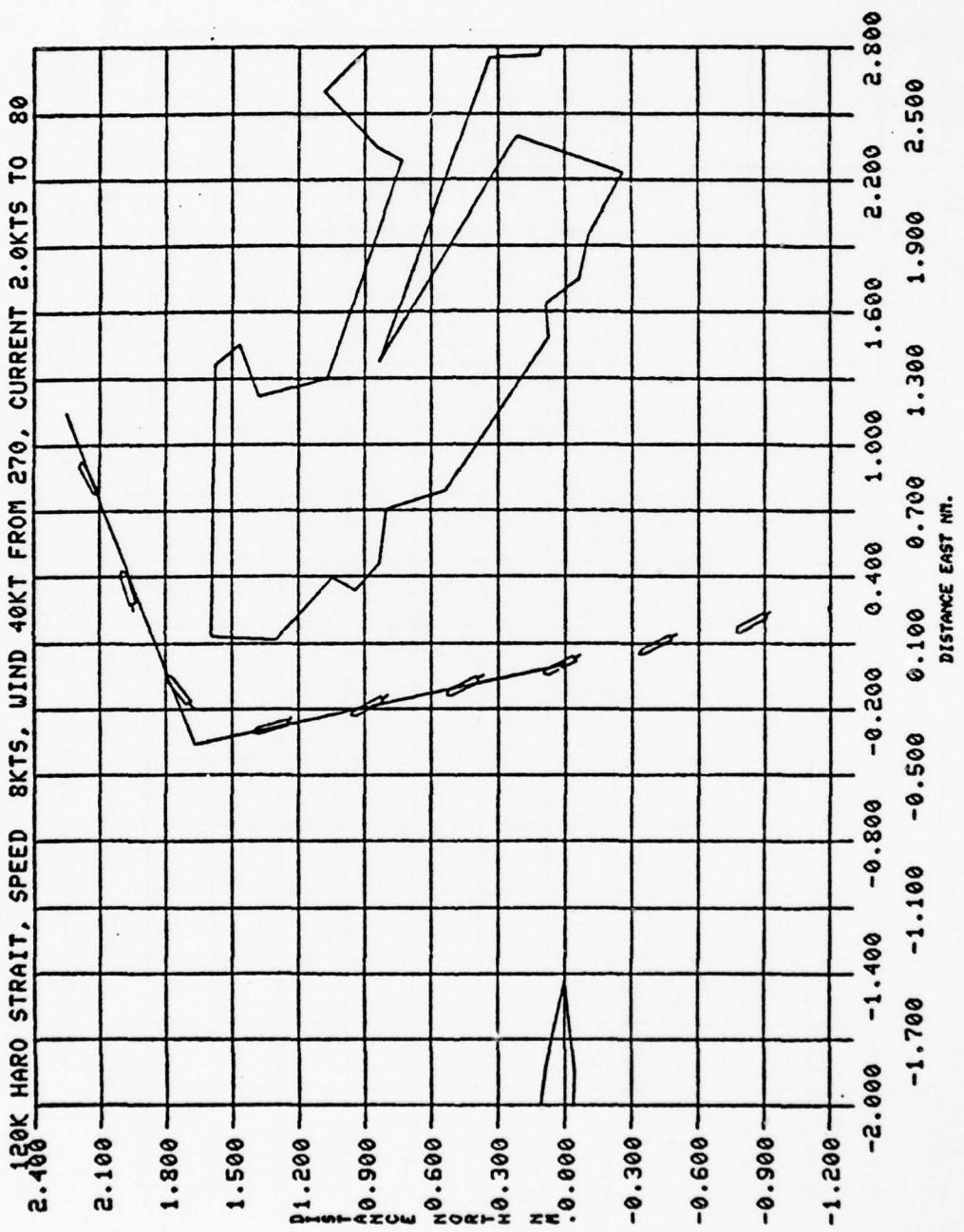




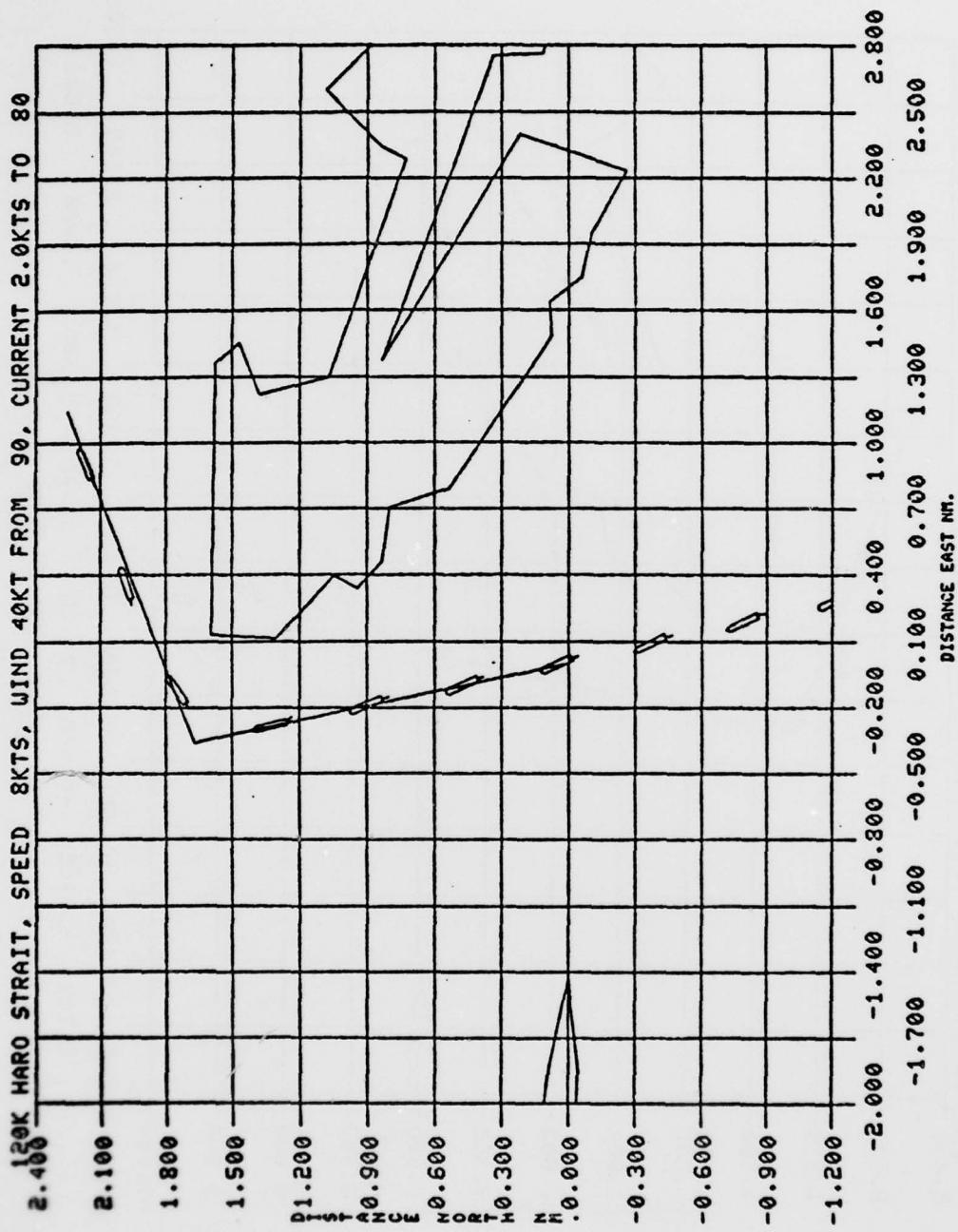
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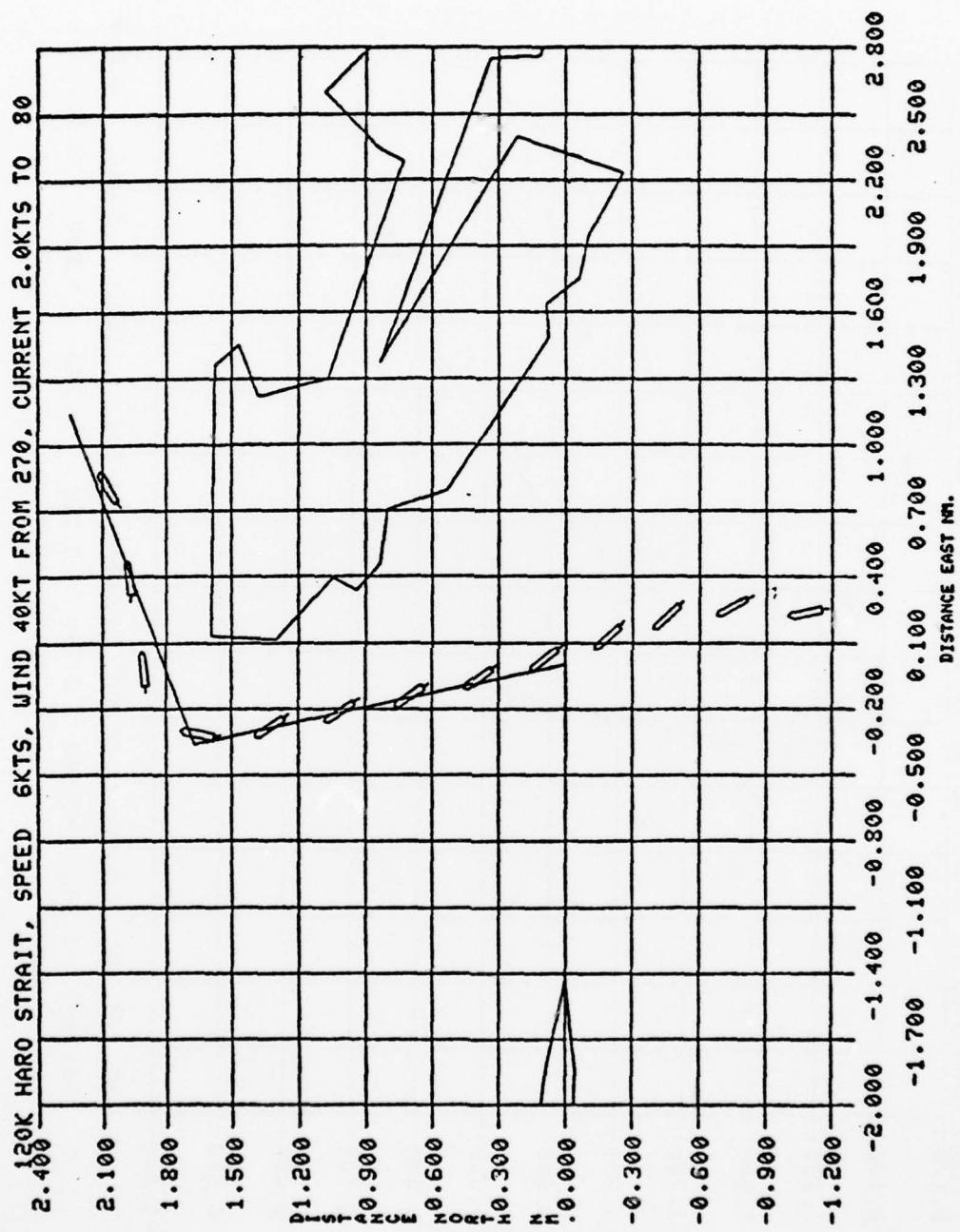
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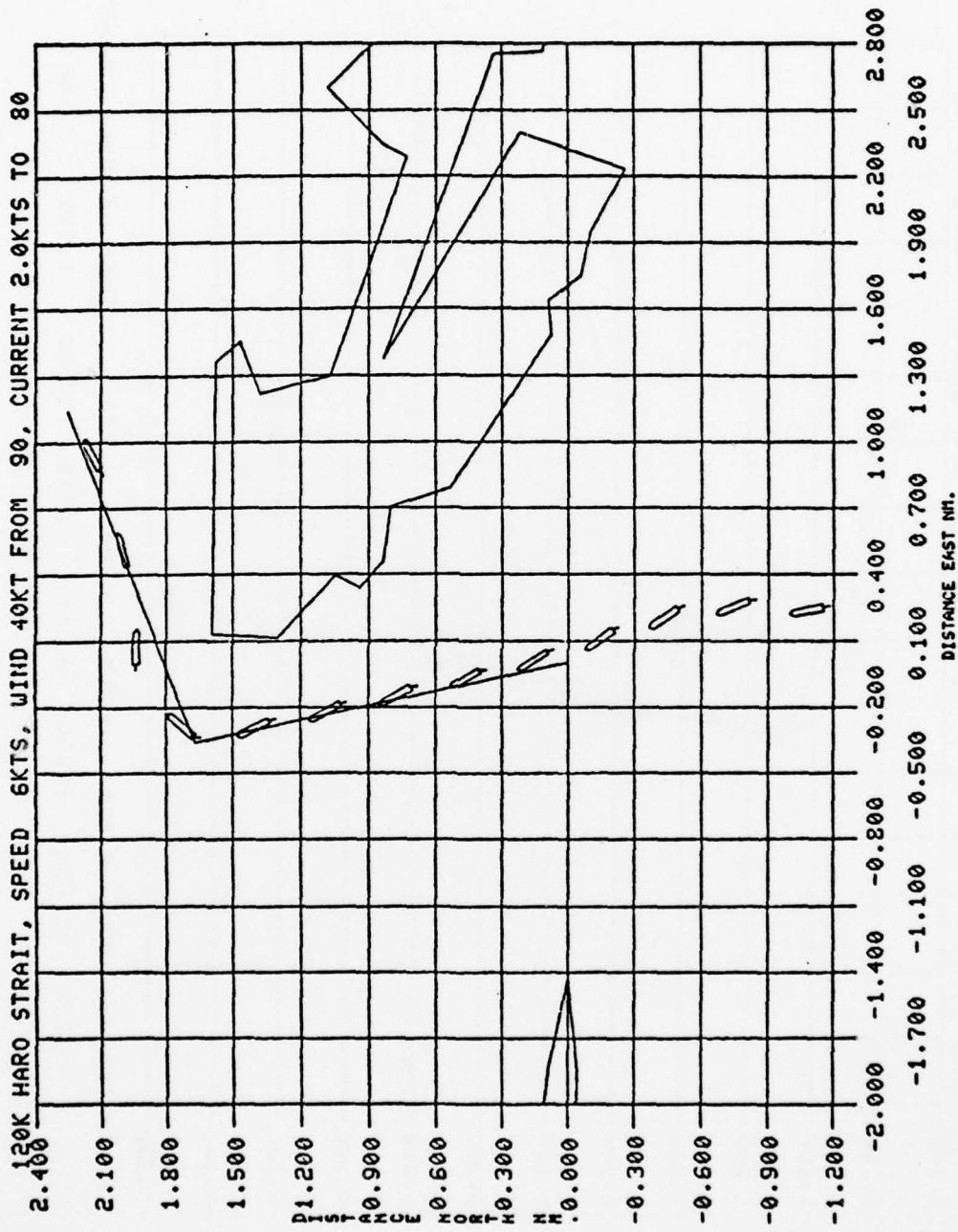
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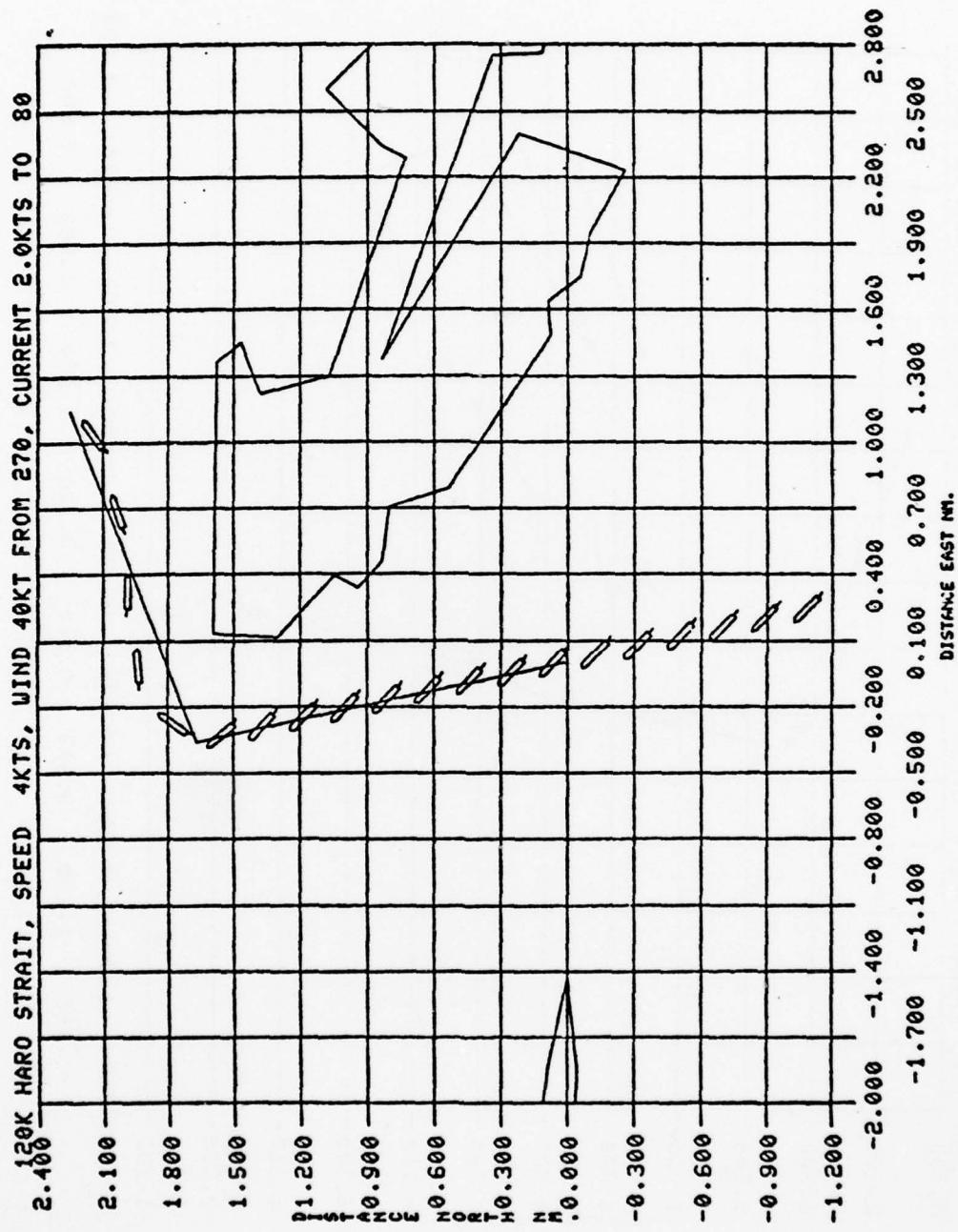
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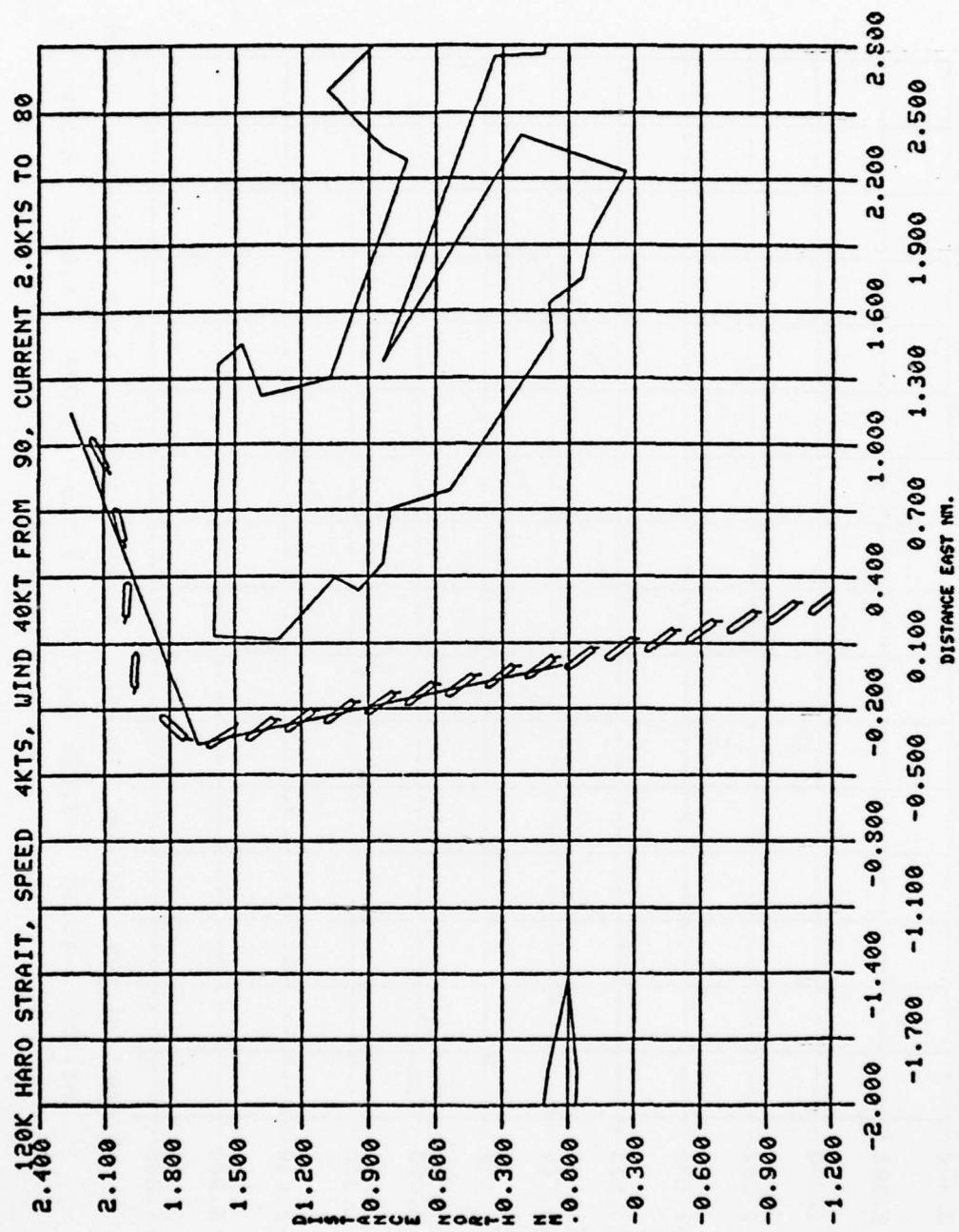
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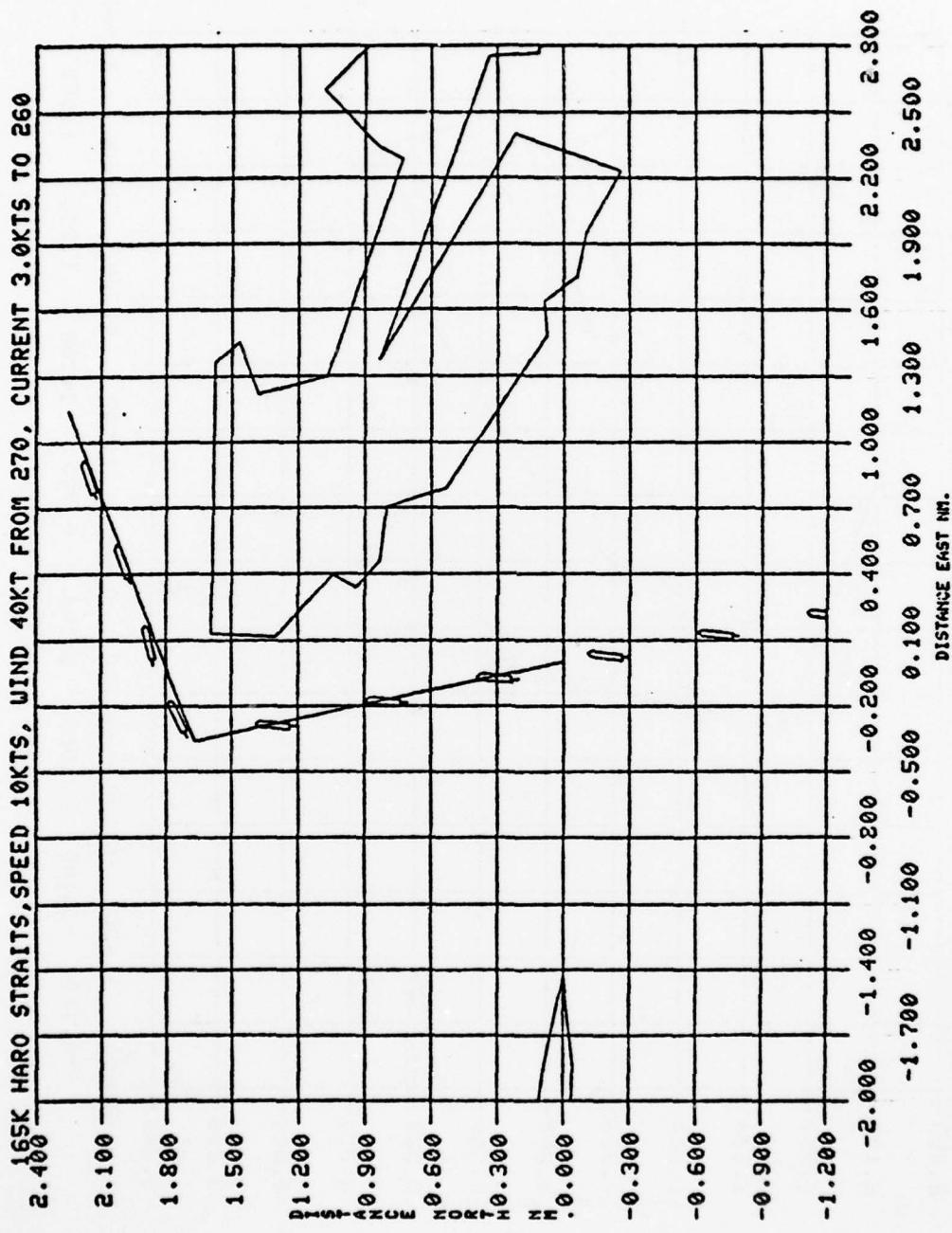
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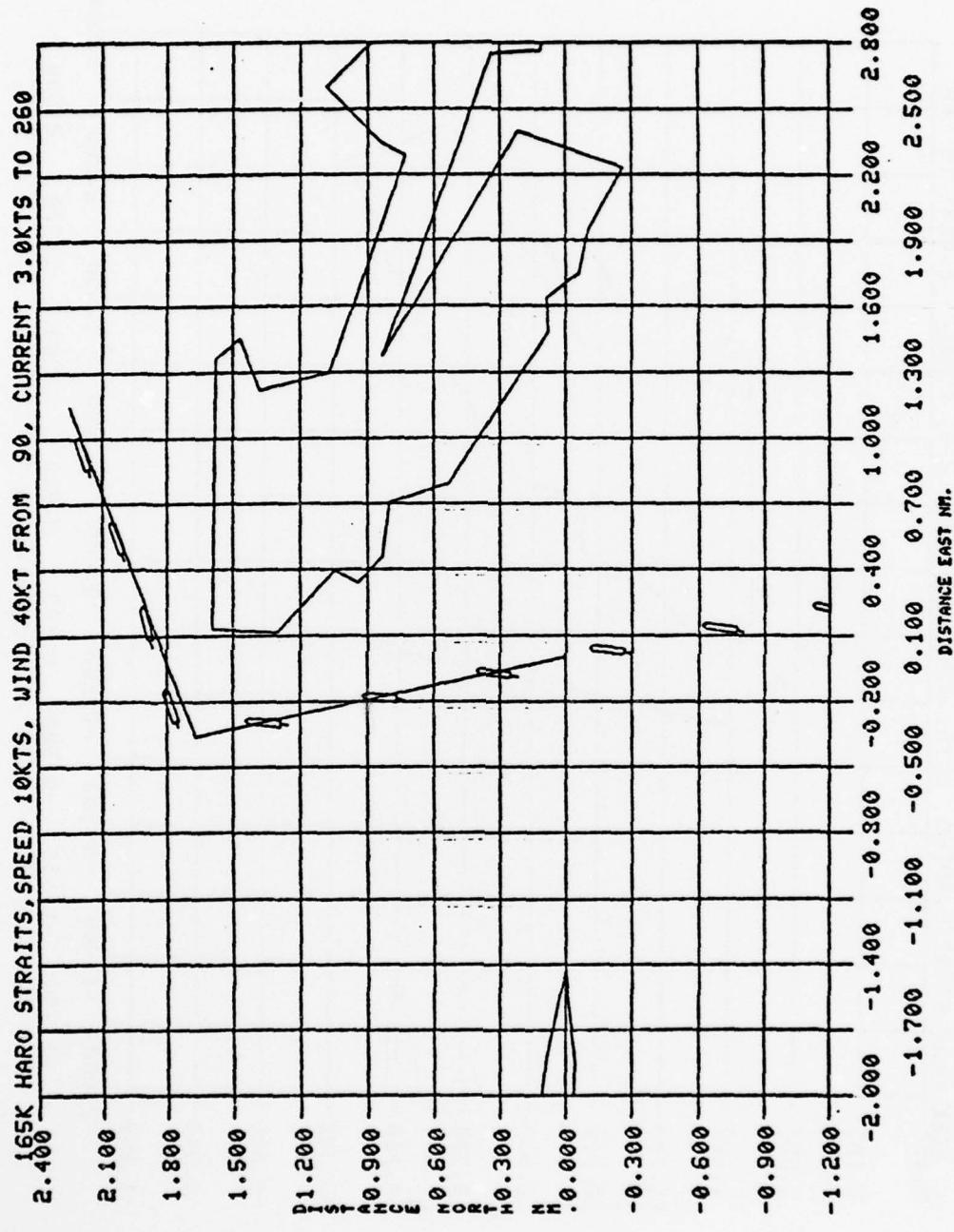


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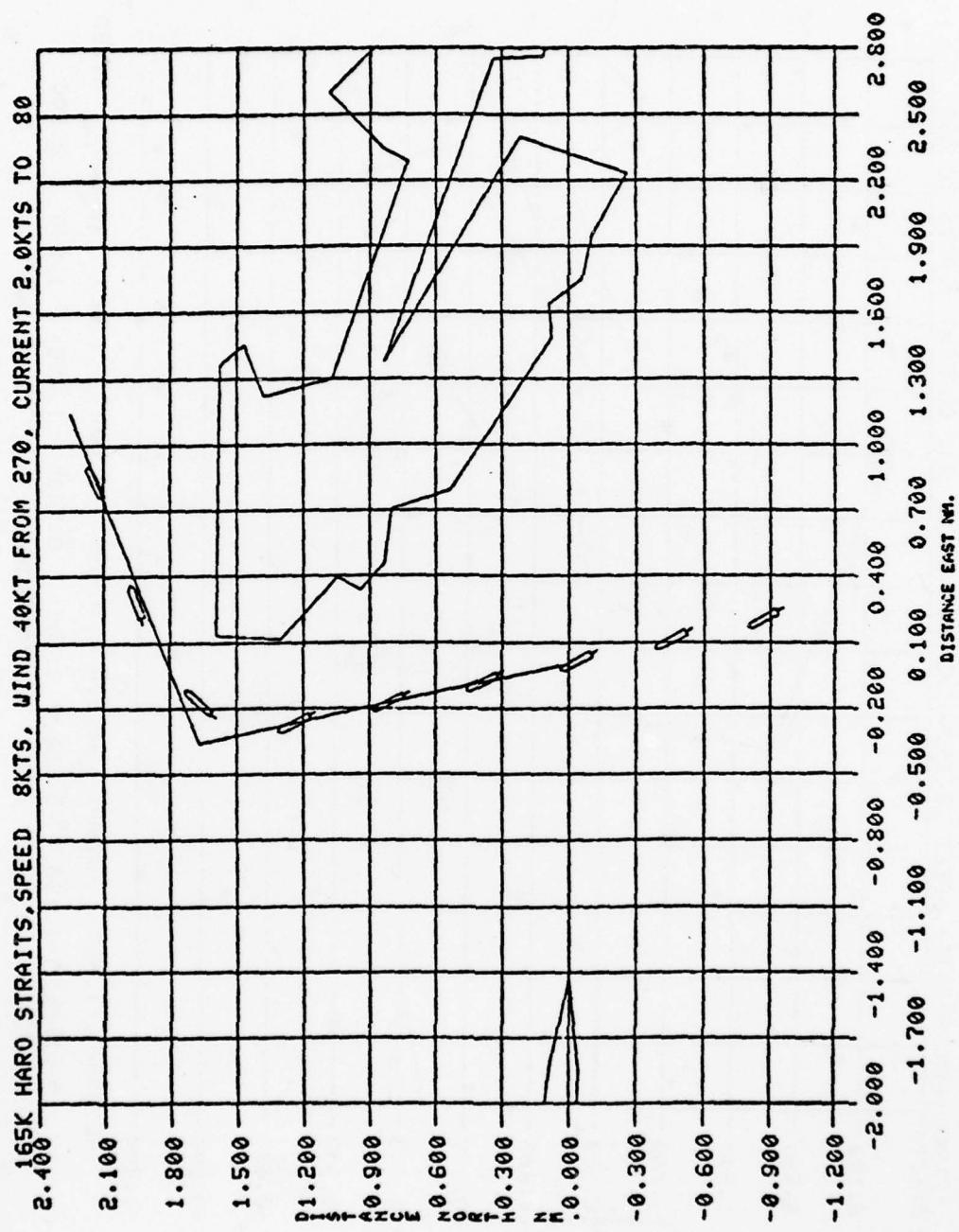


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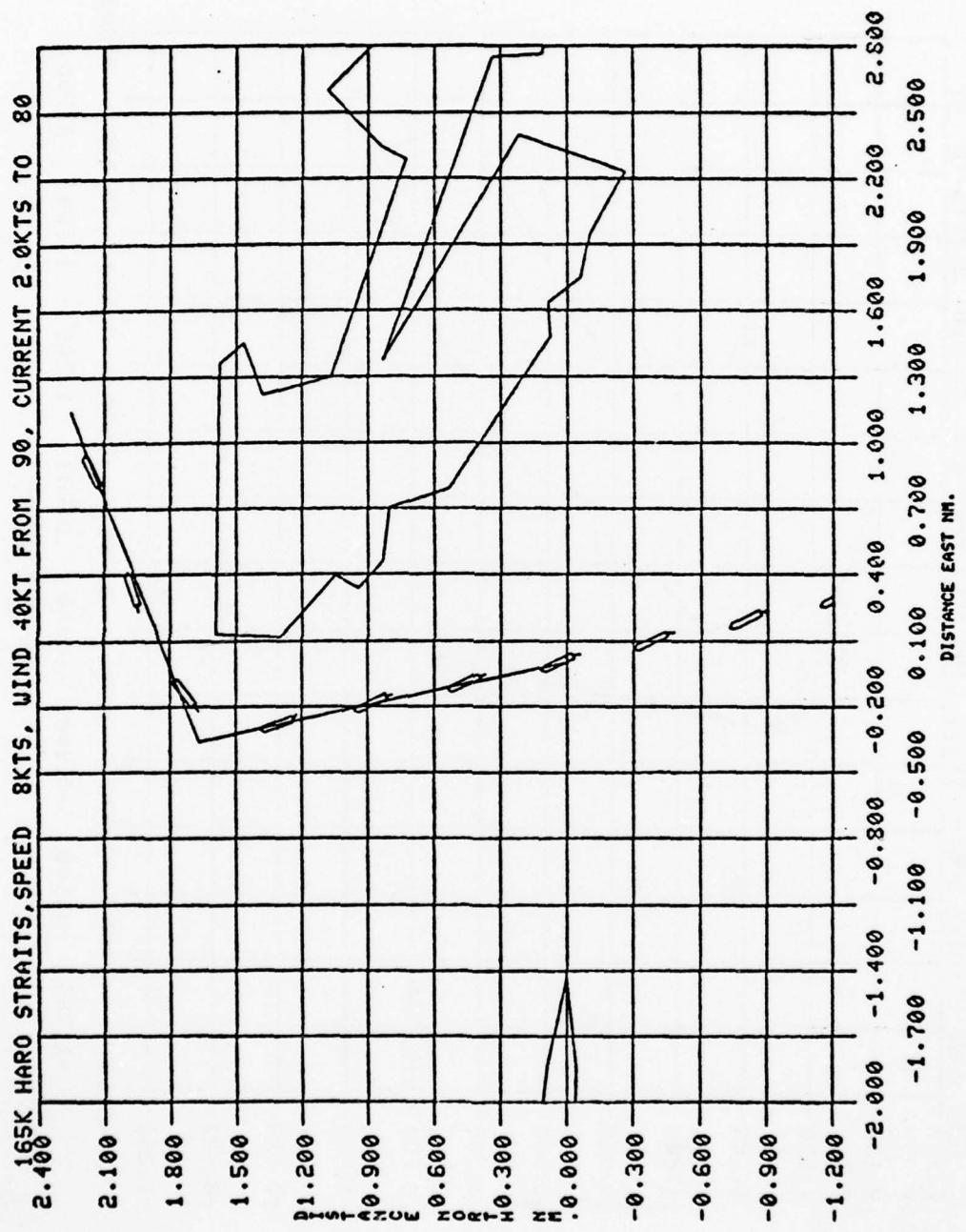




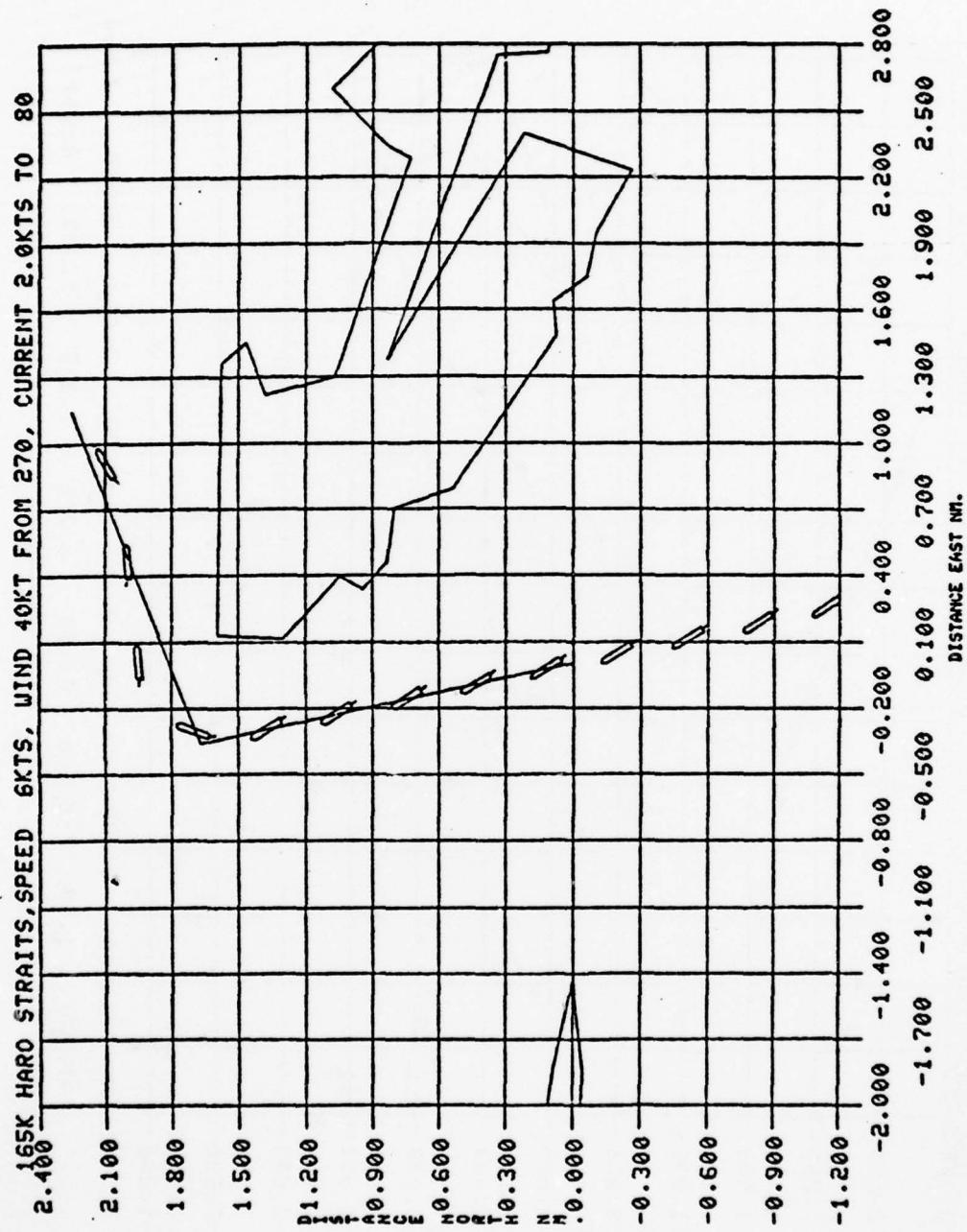
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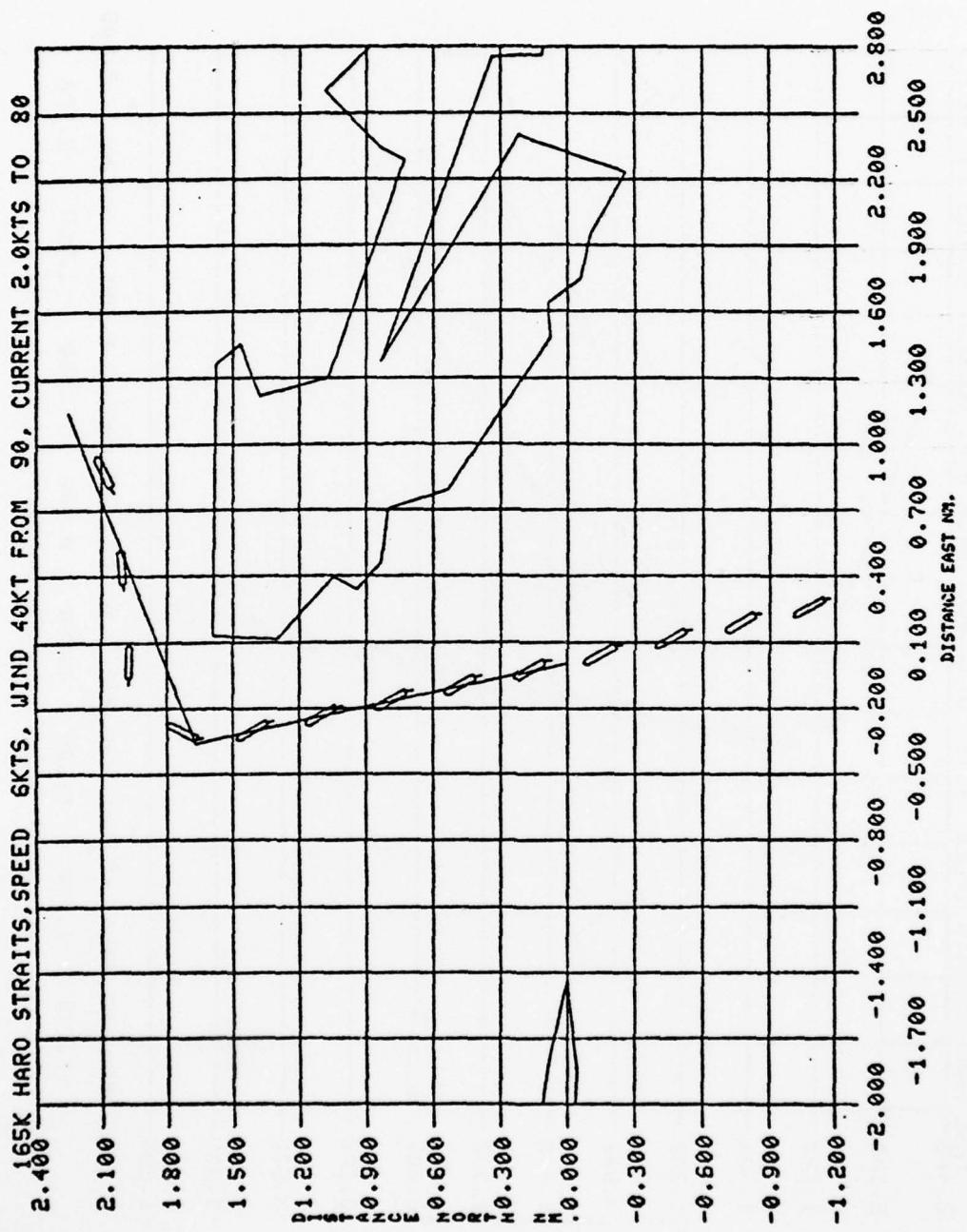
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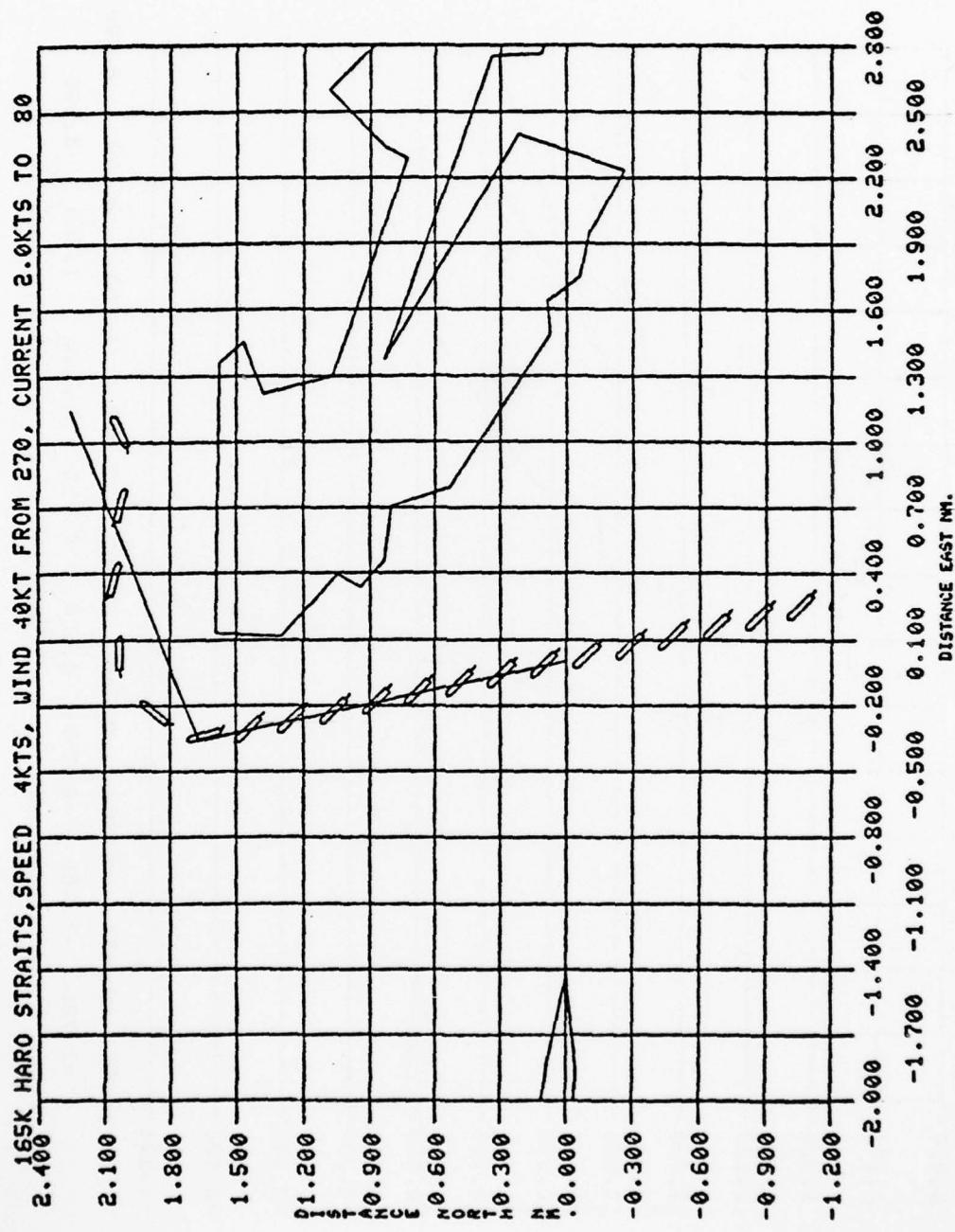
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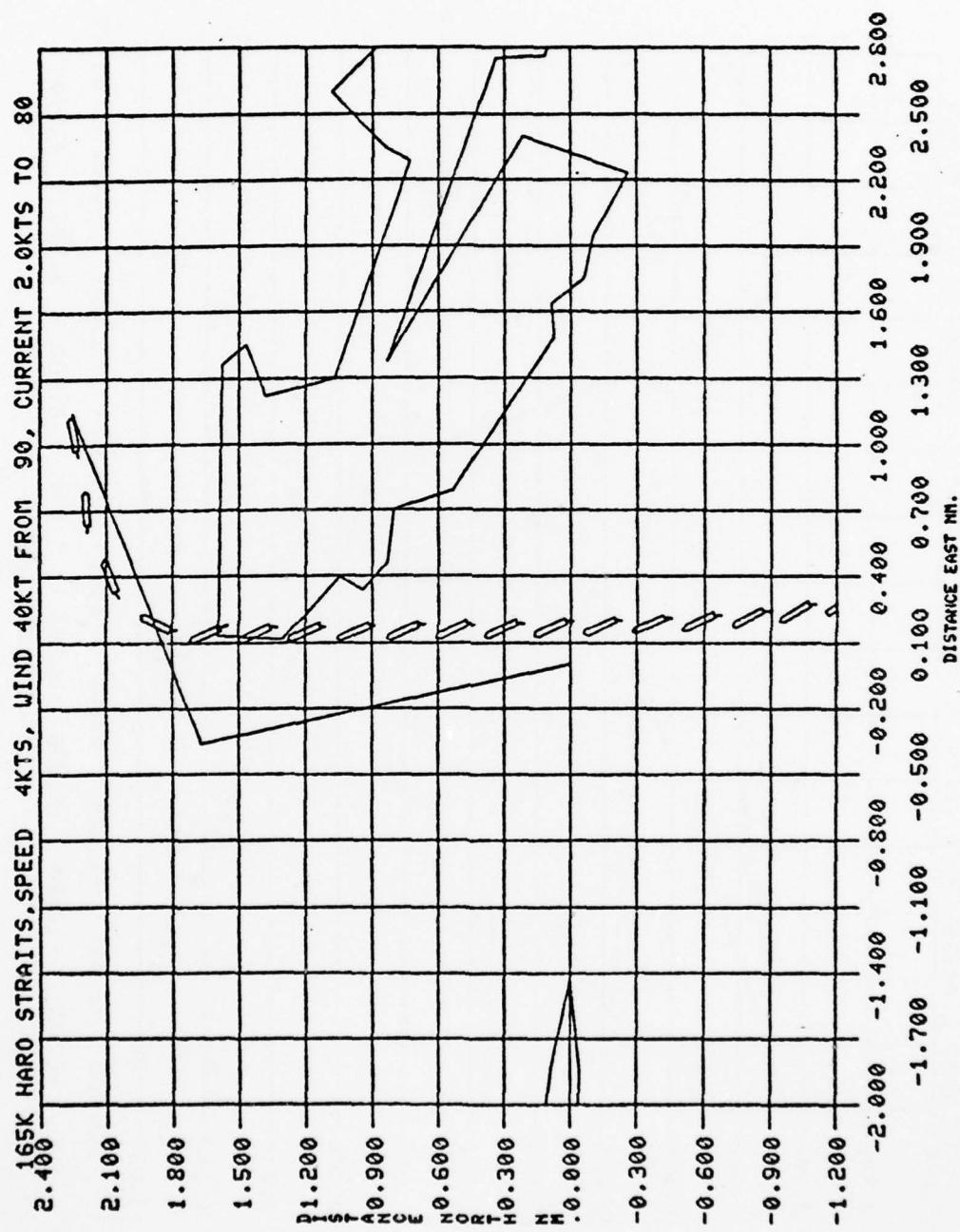
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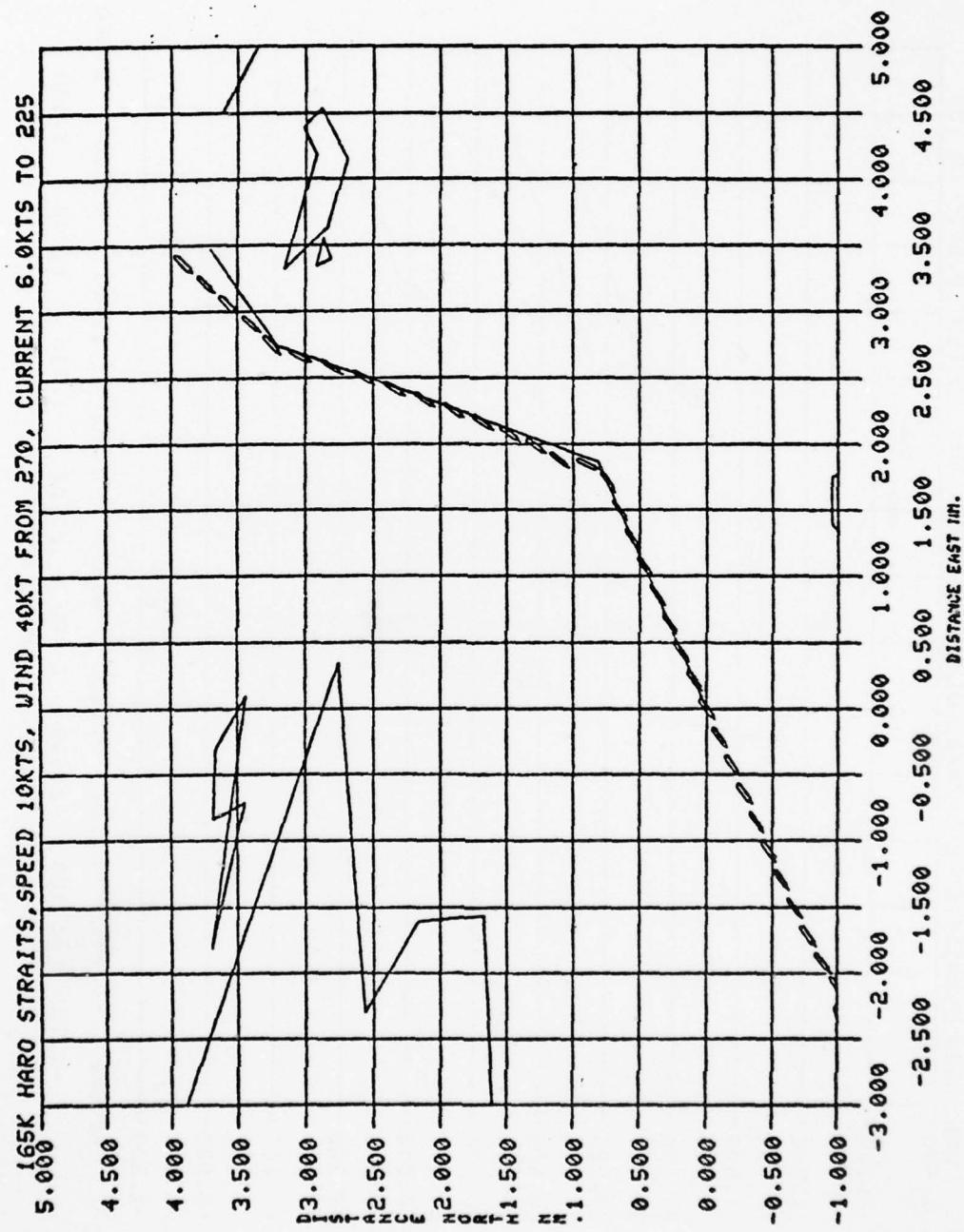
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G-114

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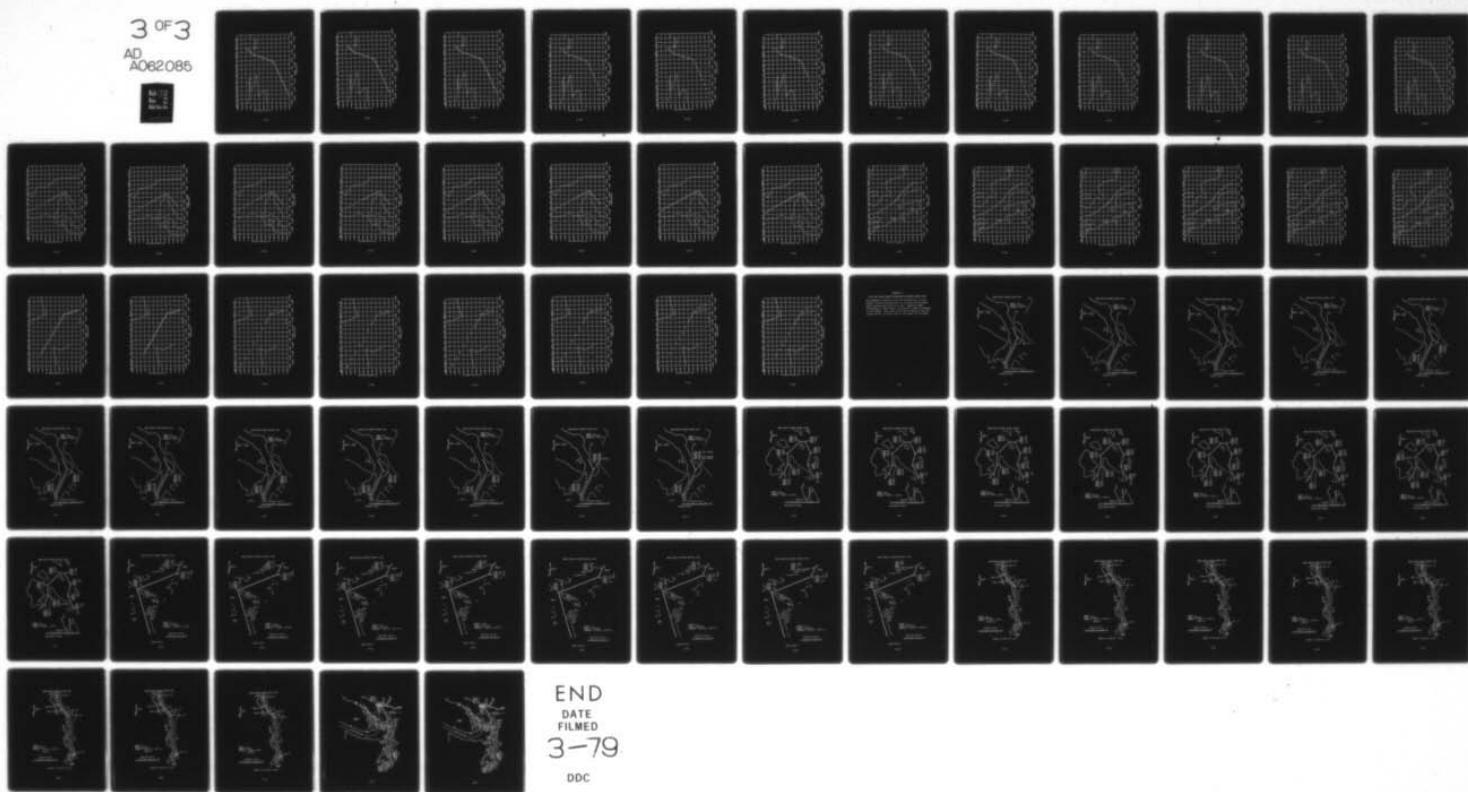
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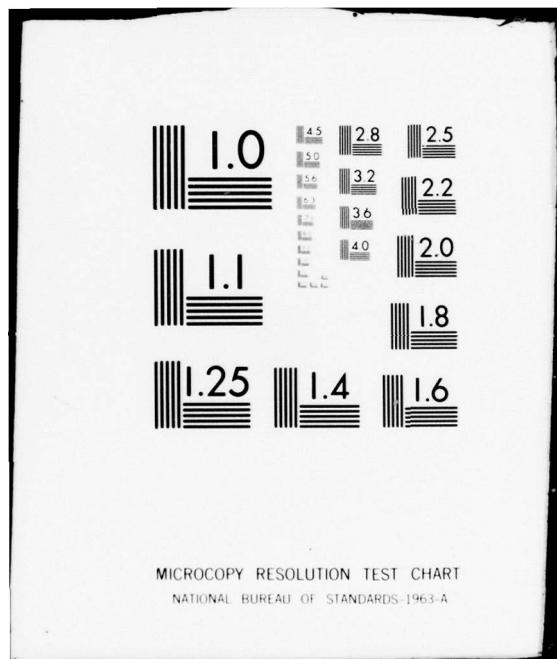
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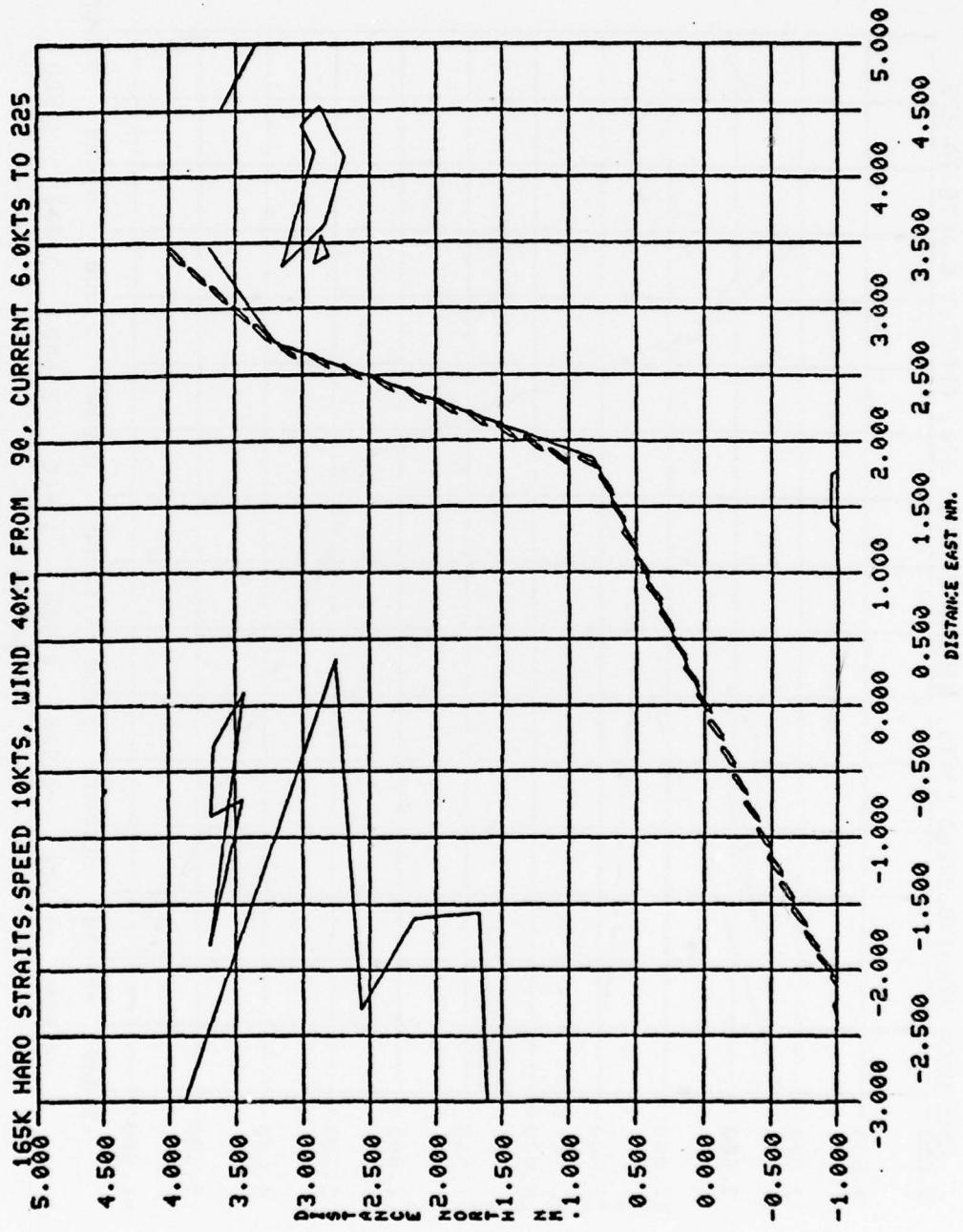
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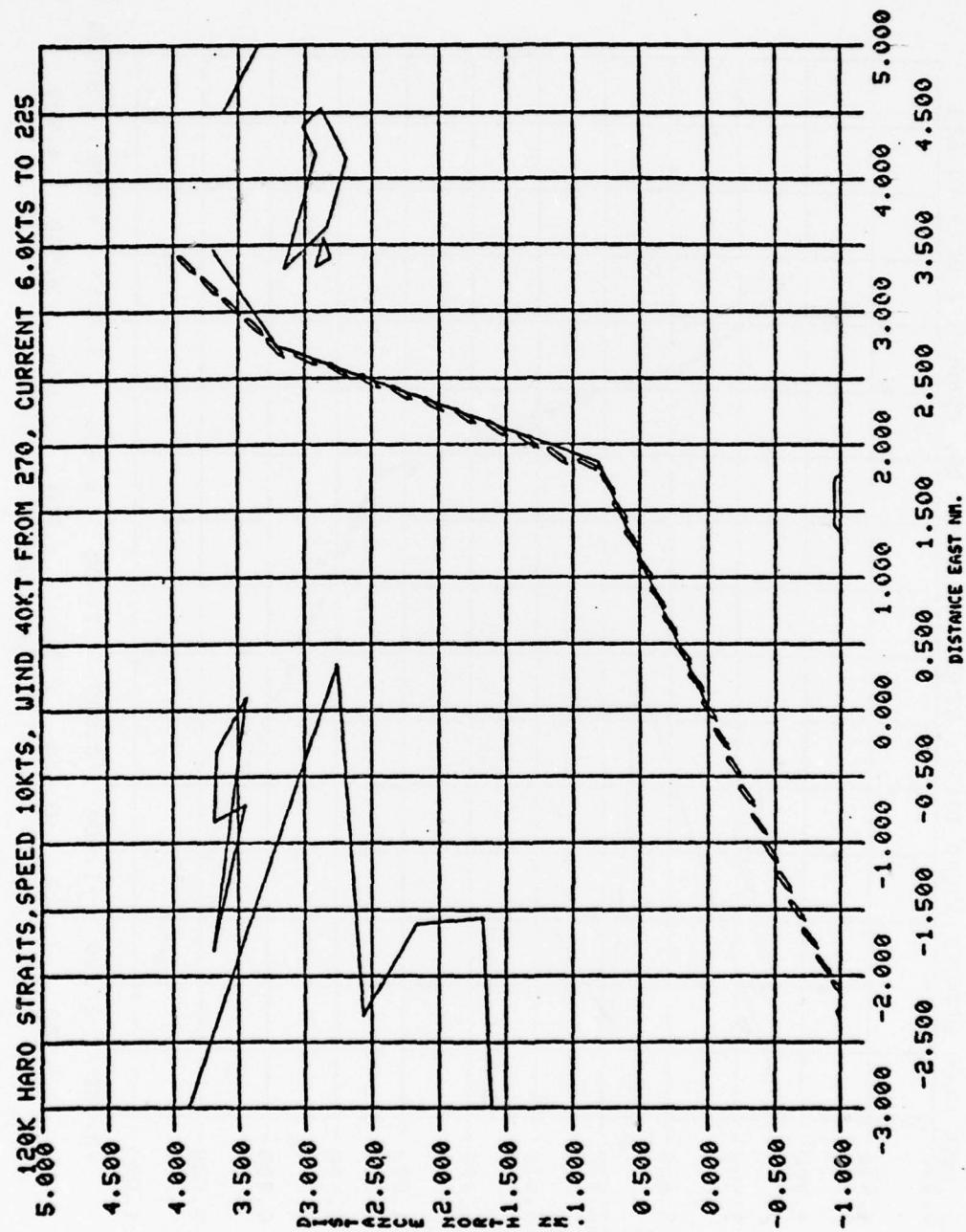
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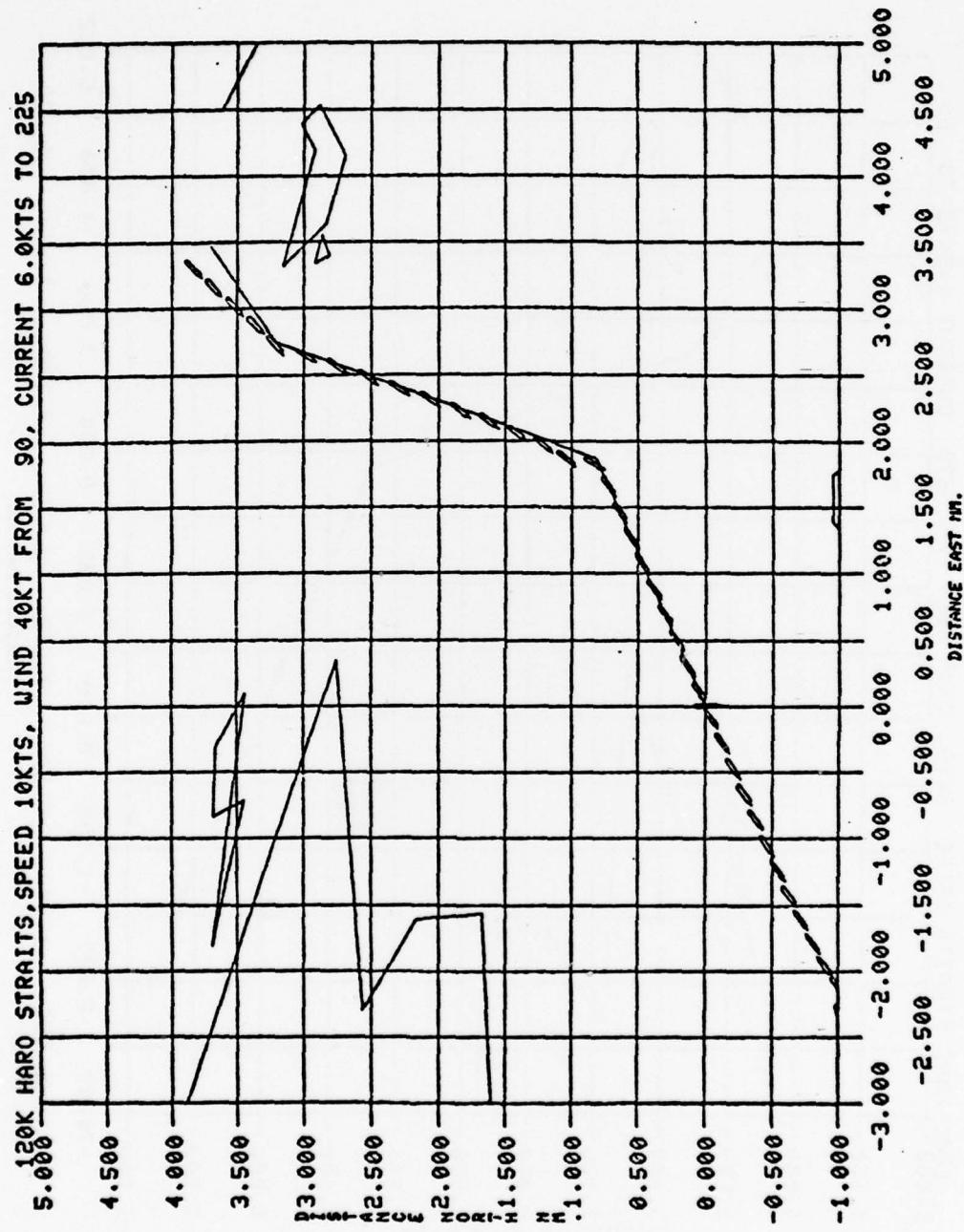
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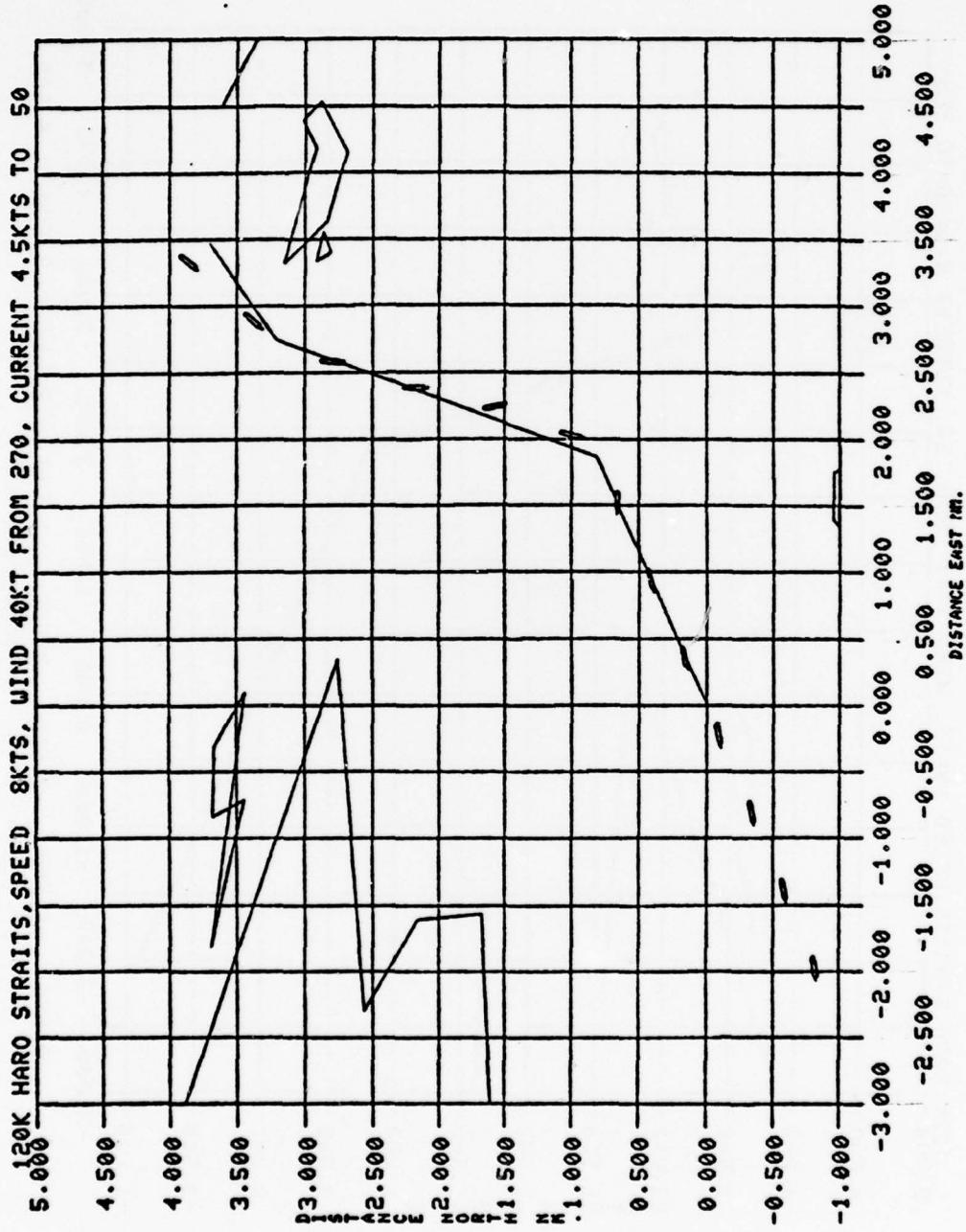




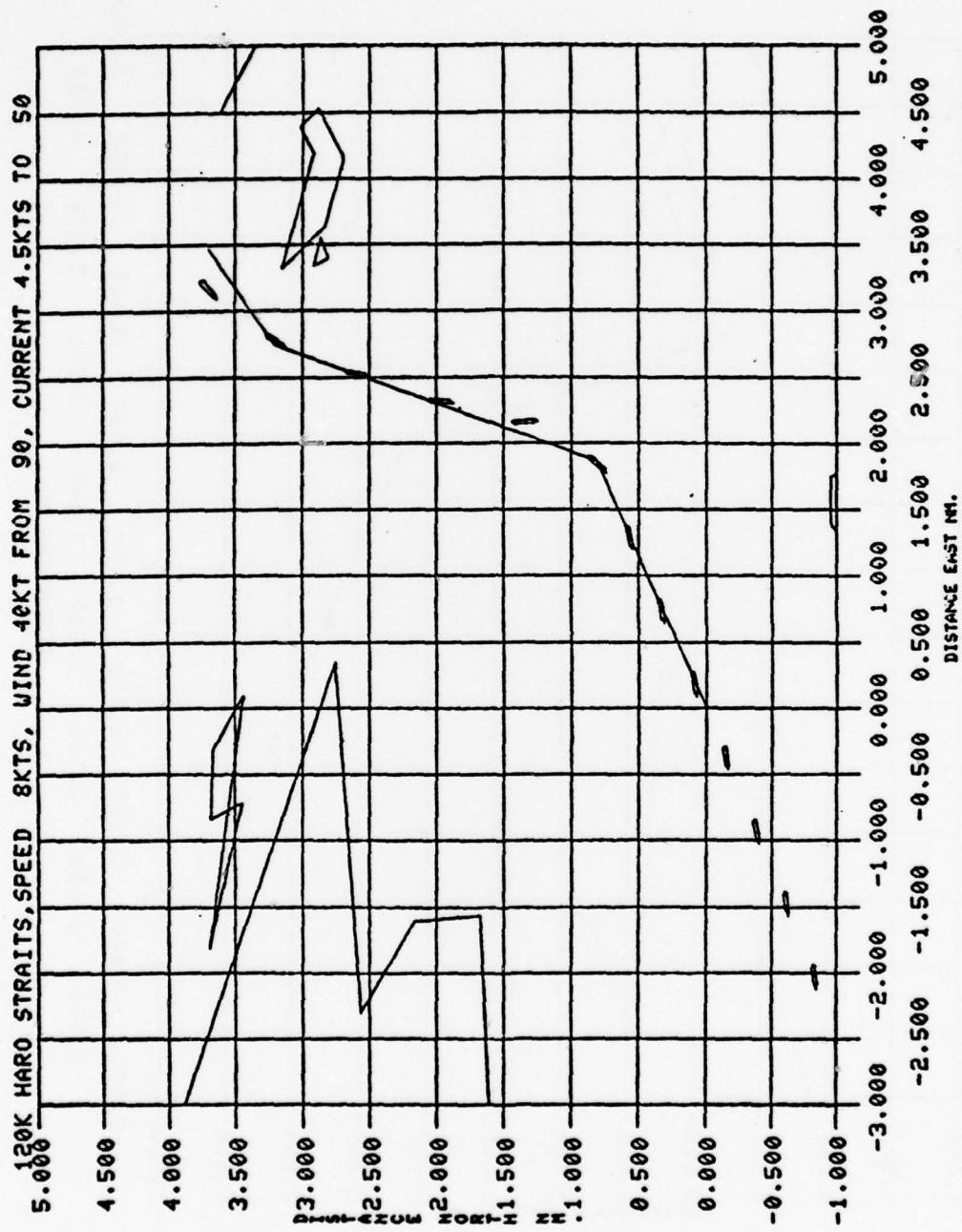
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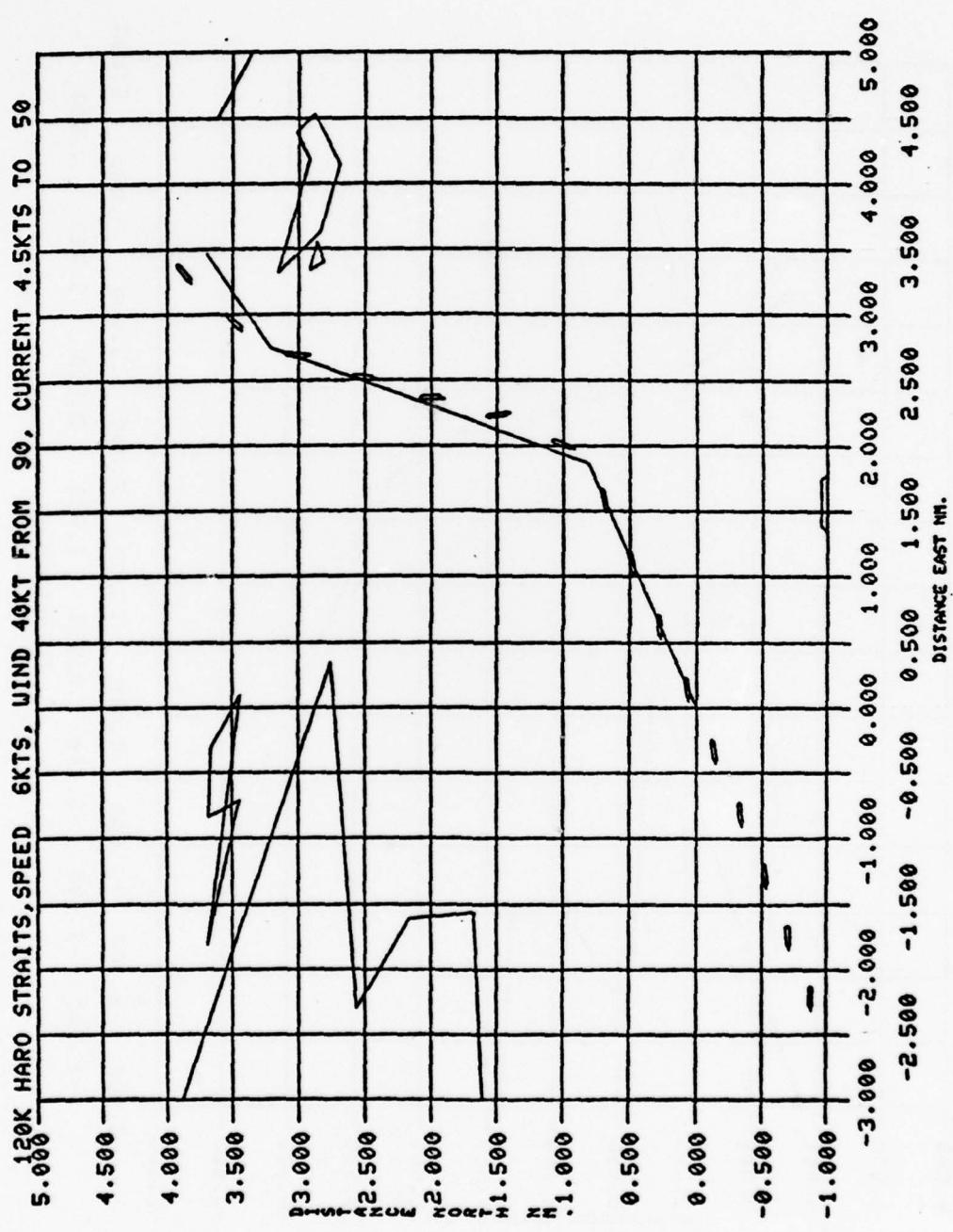
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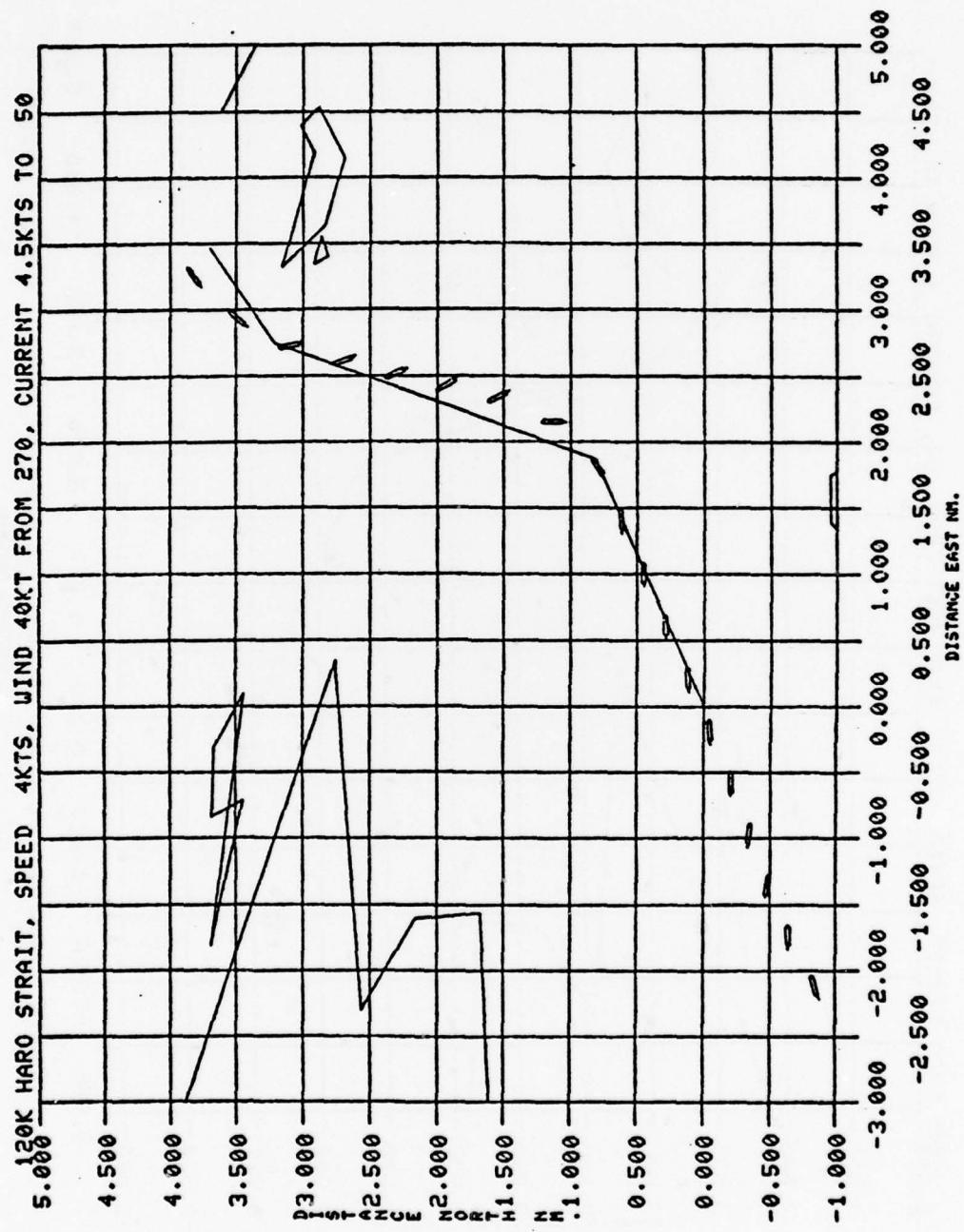
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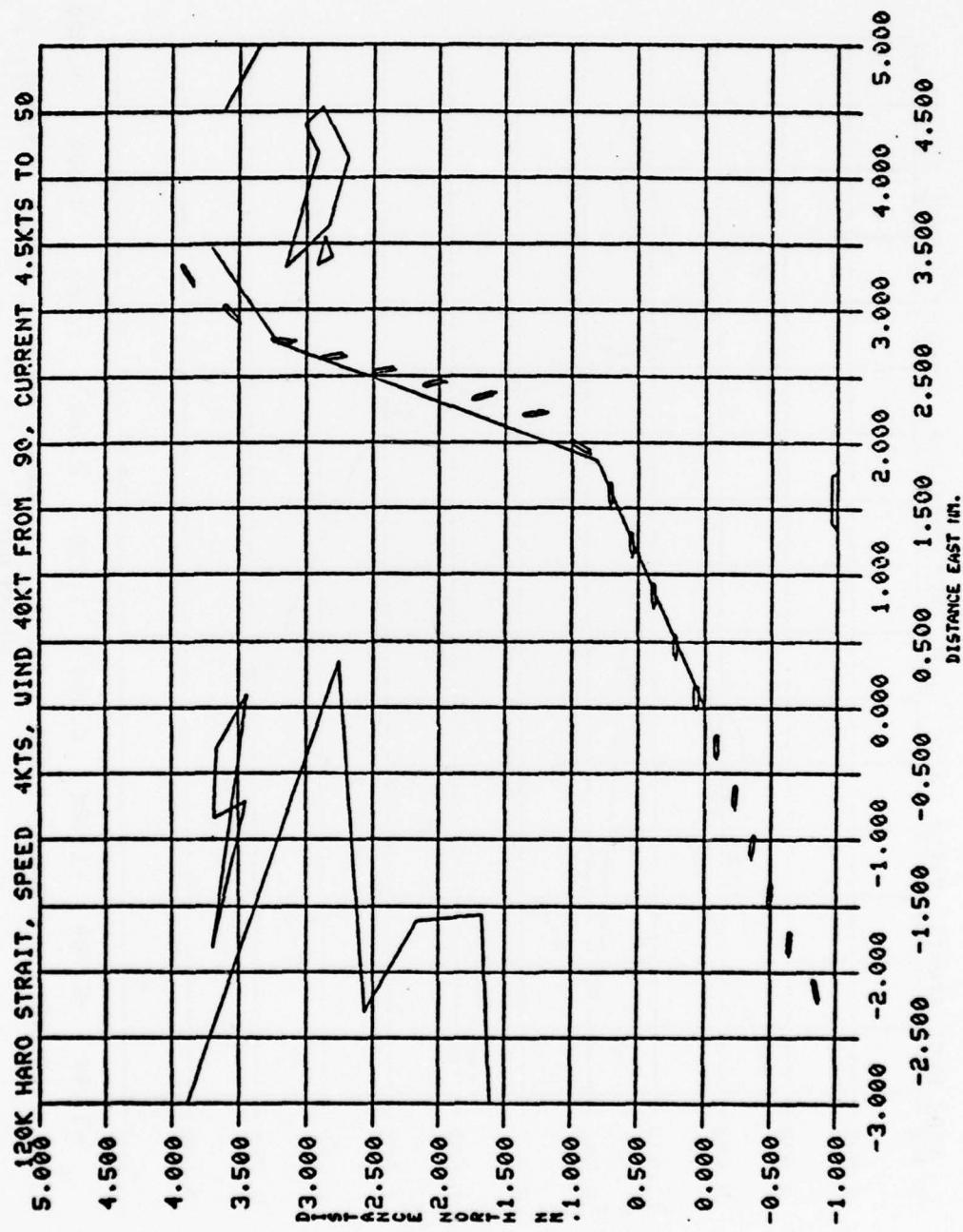


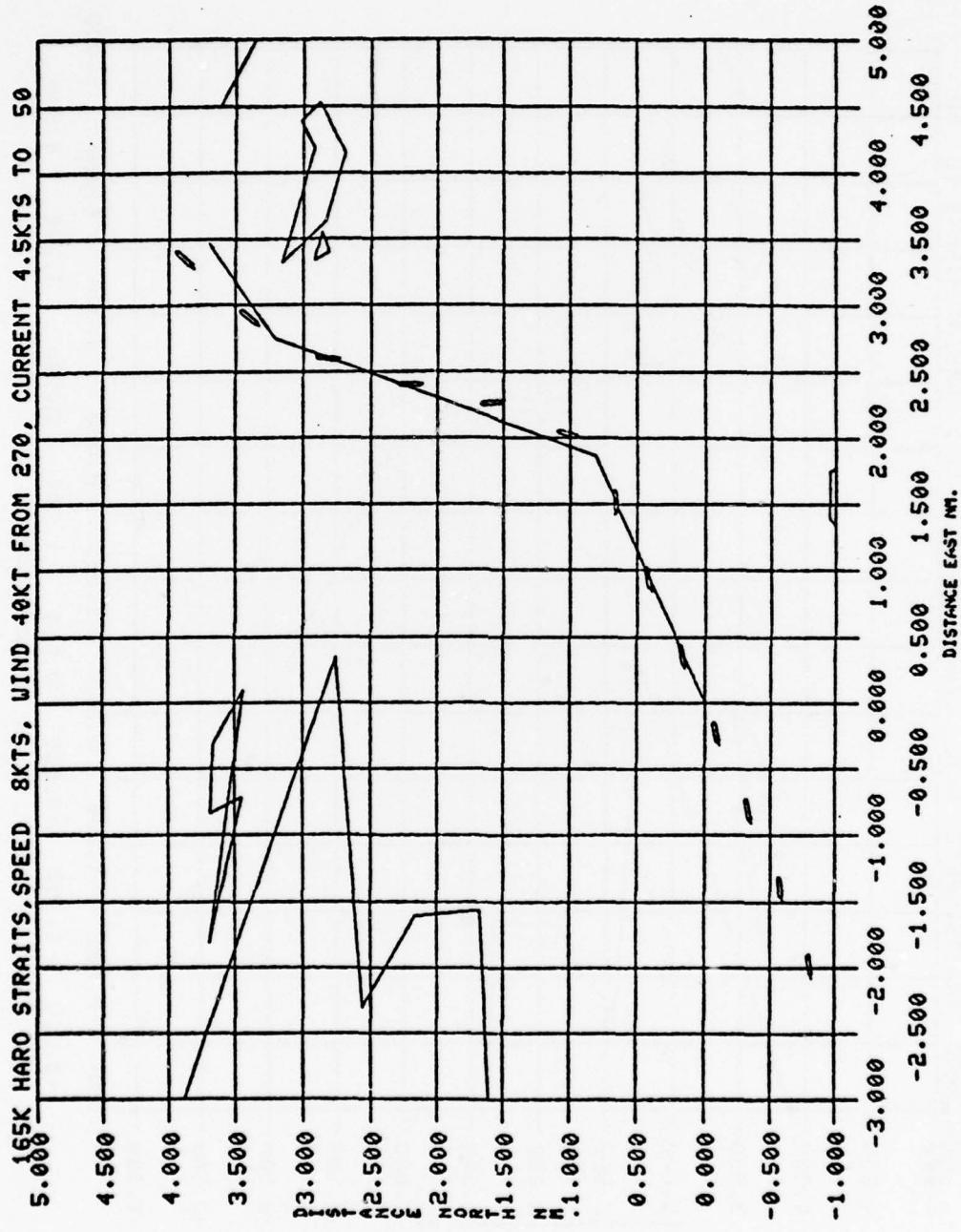
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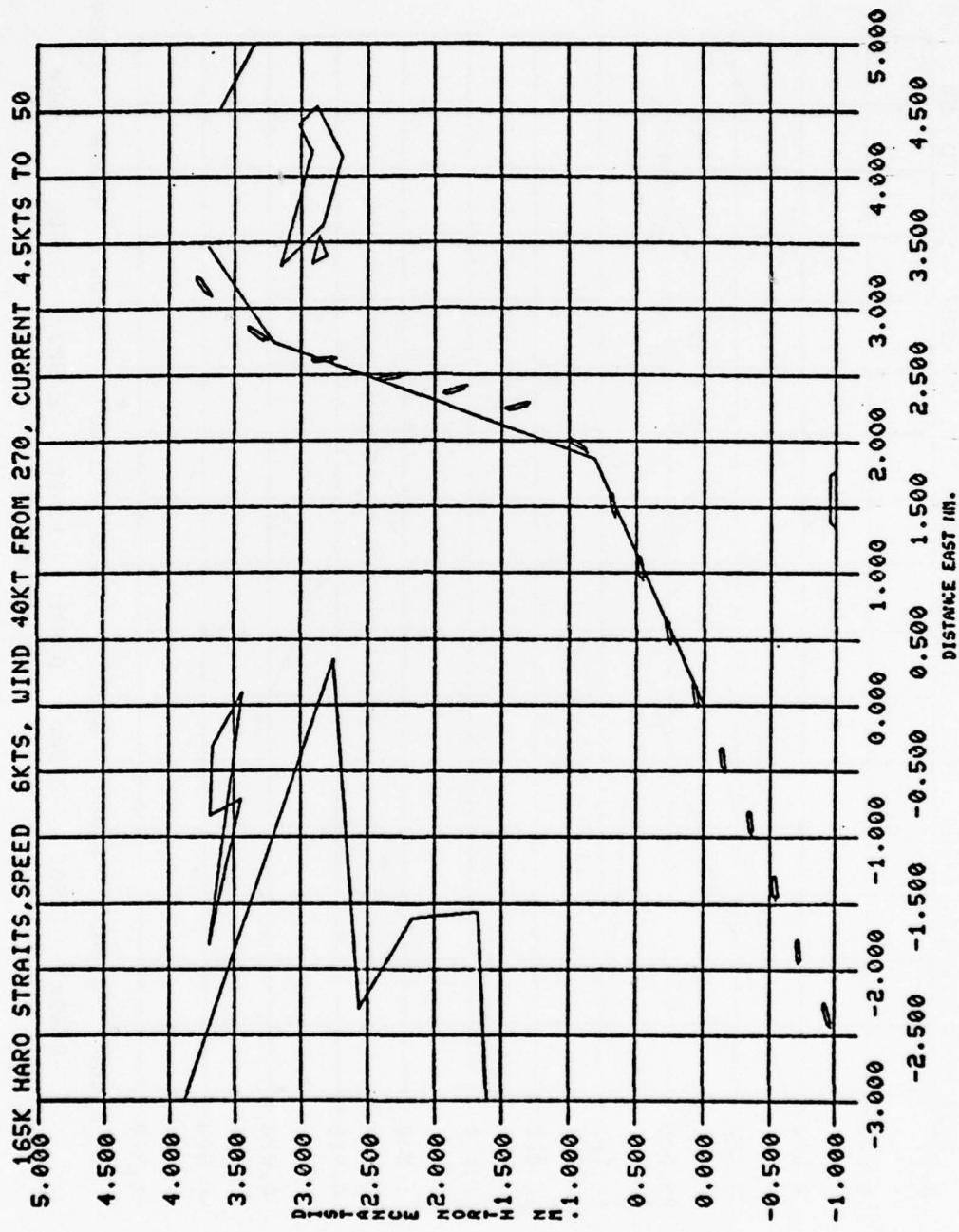


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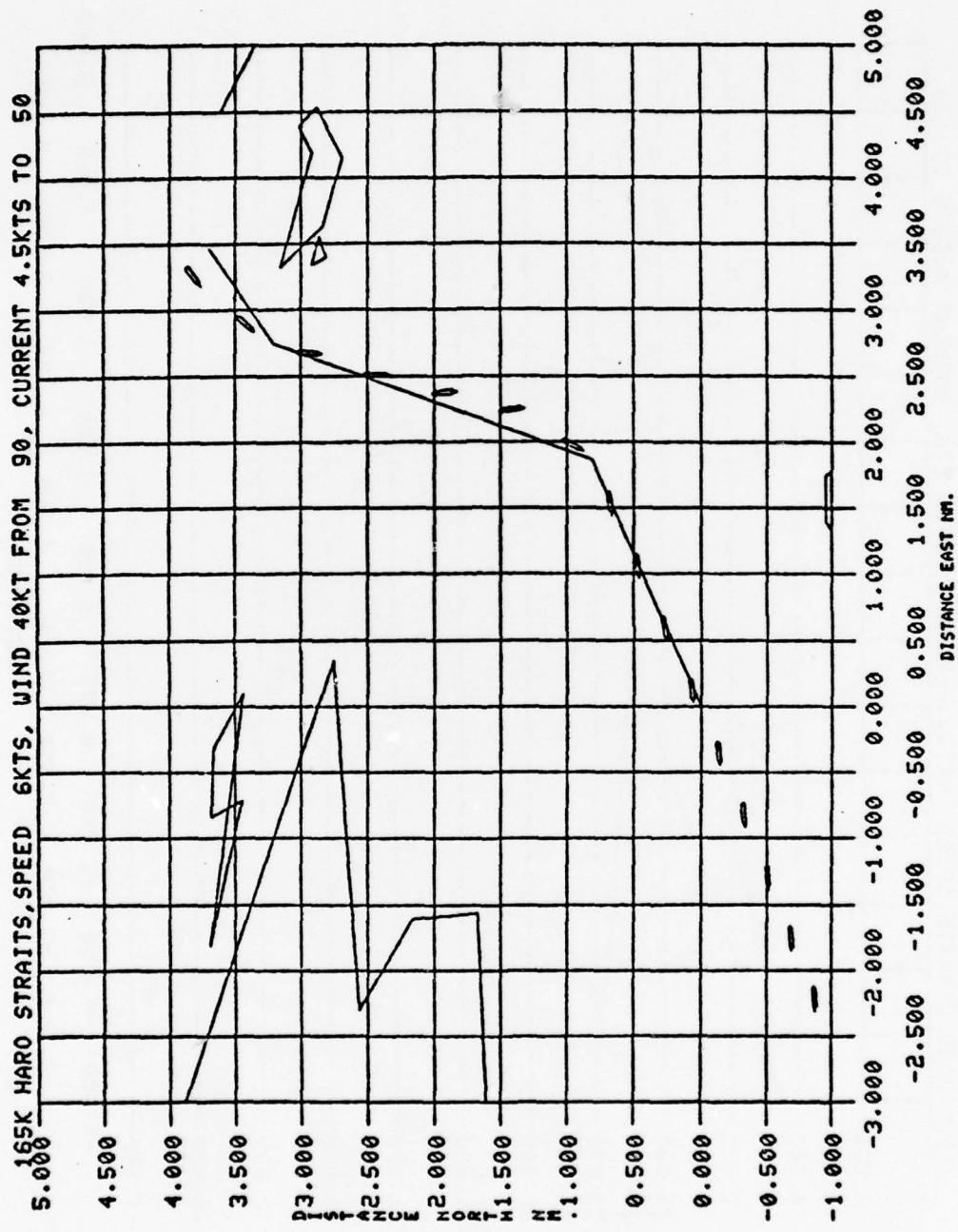




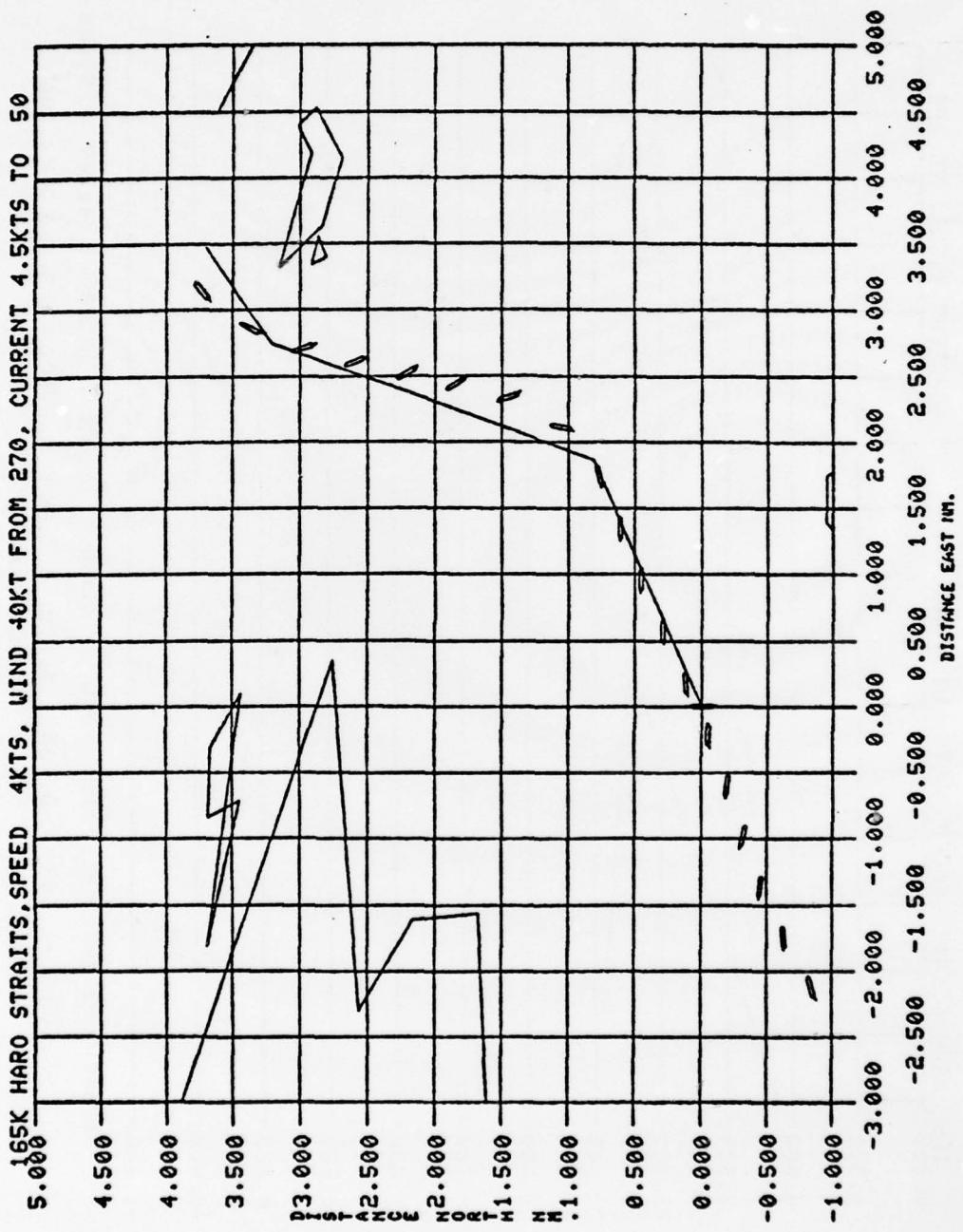


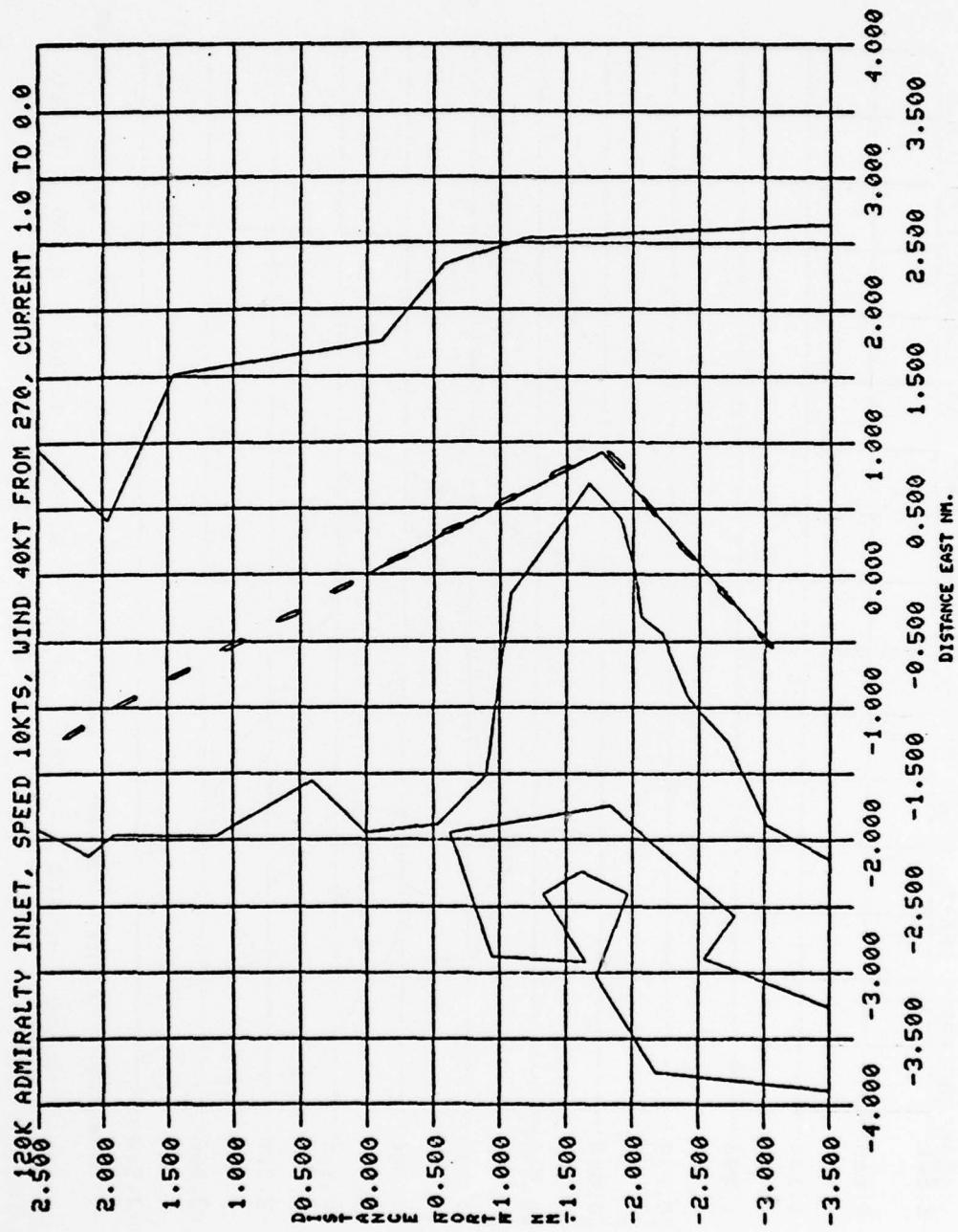


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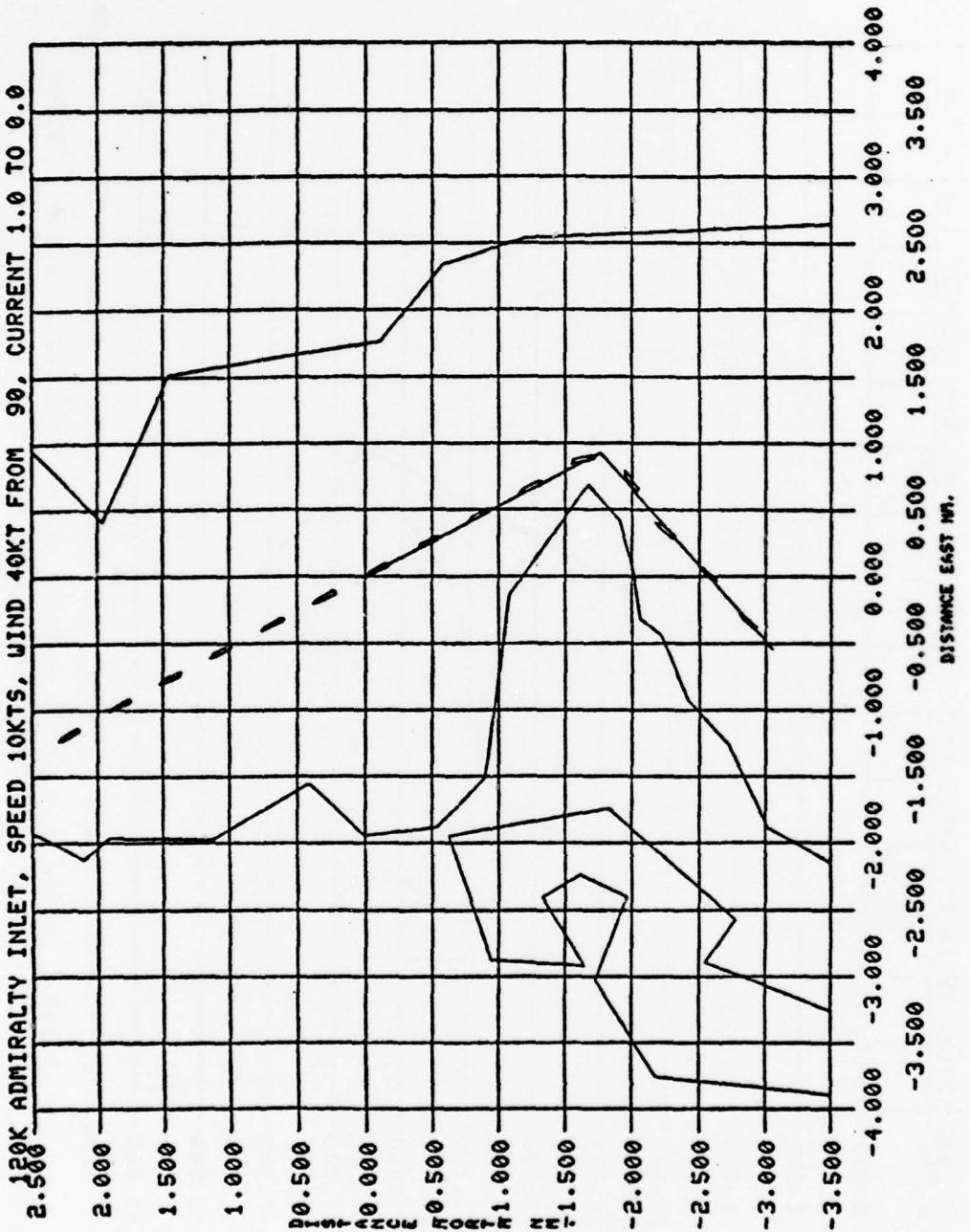


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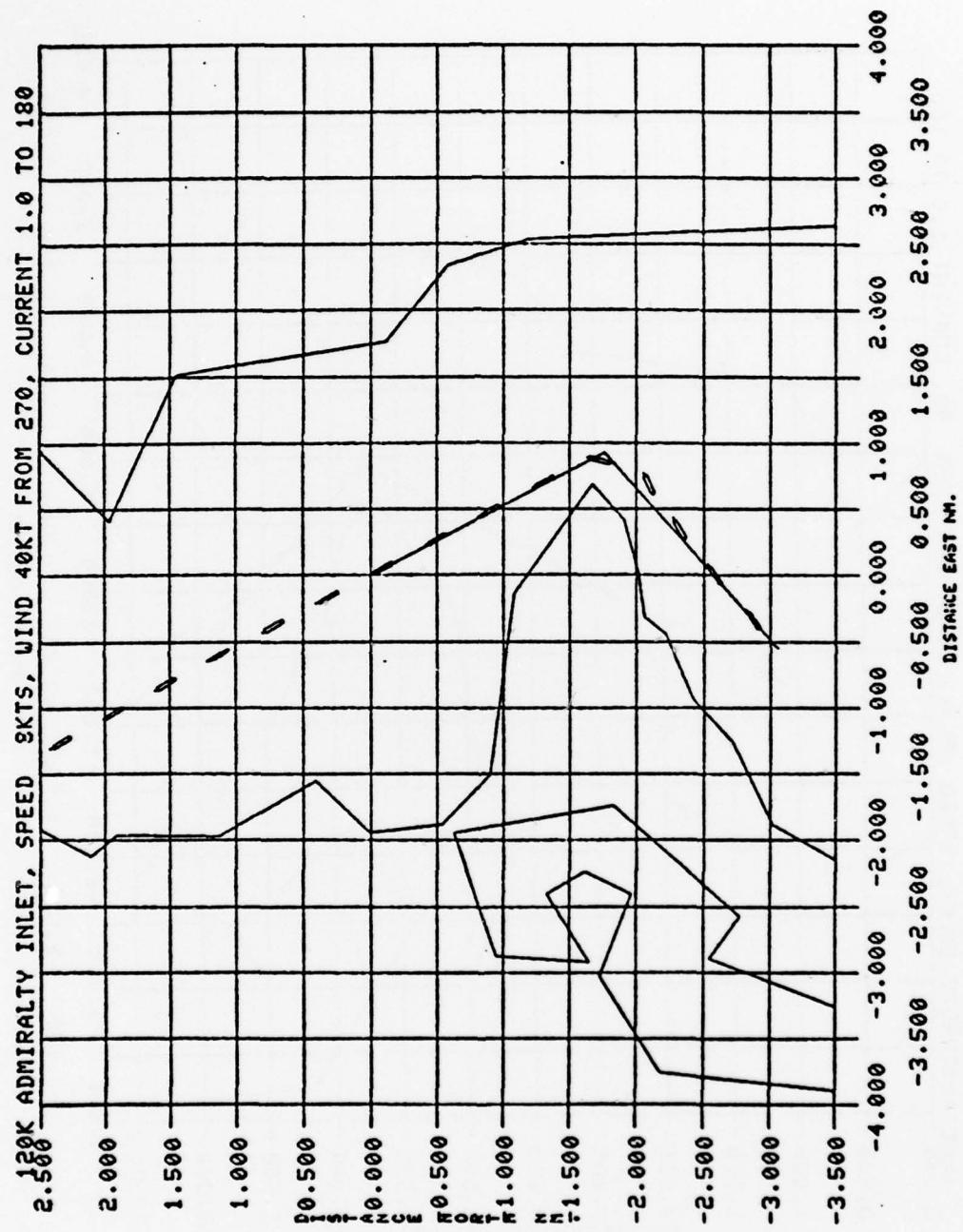




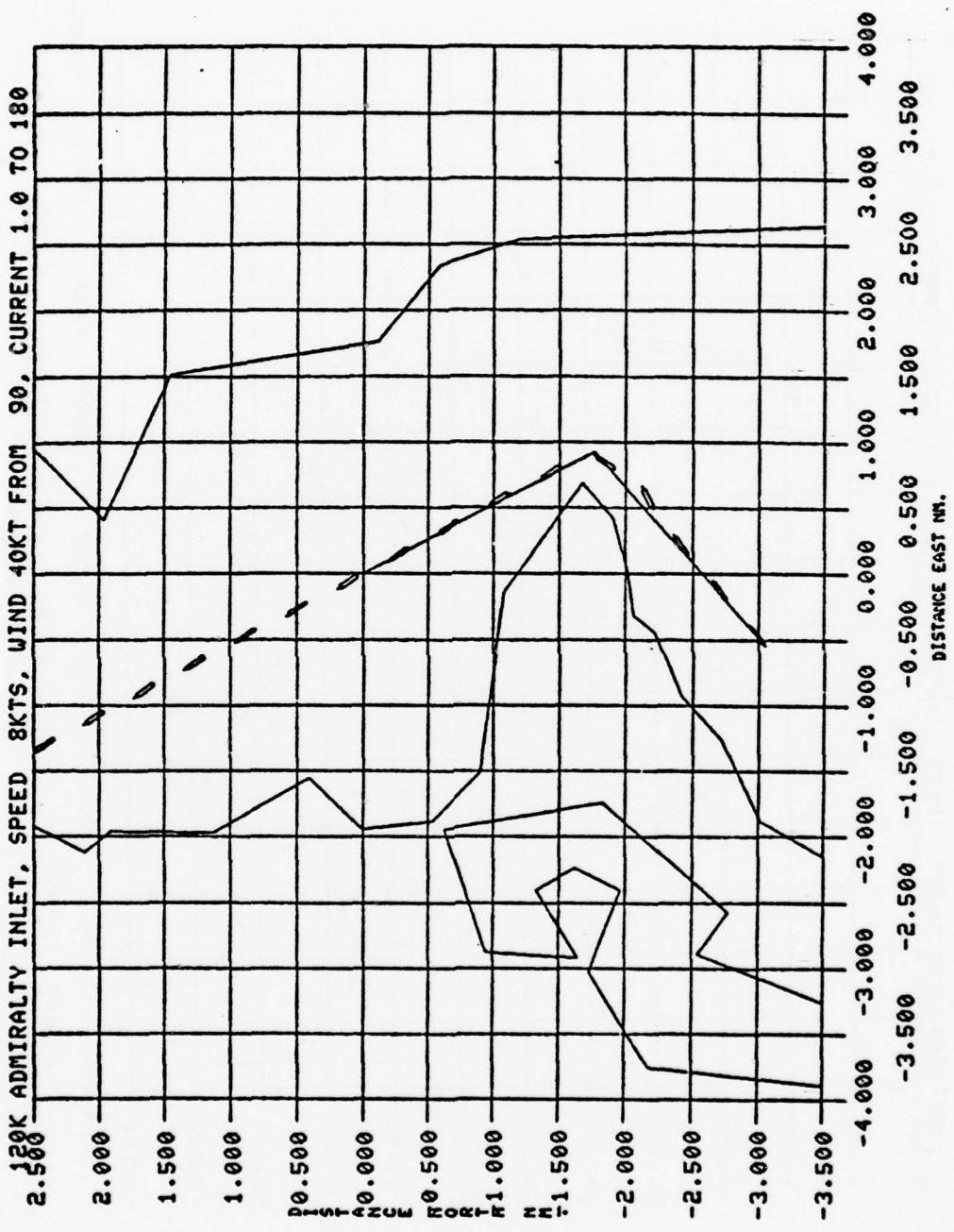
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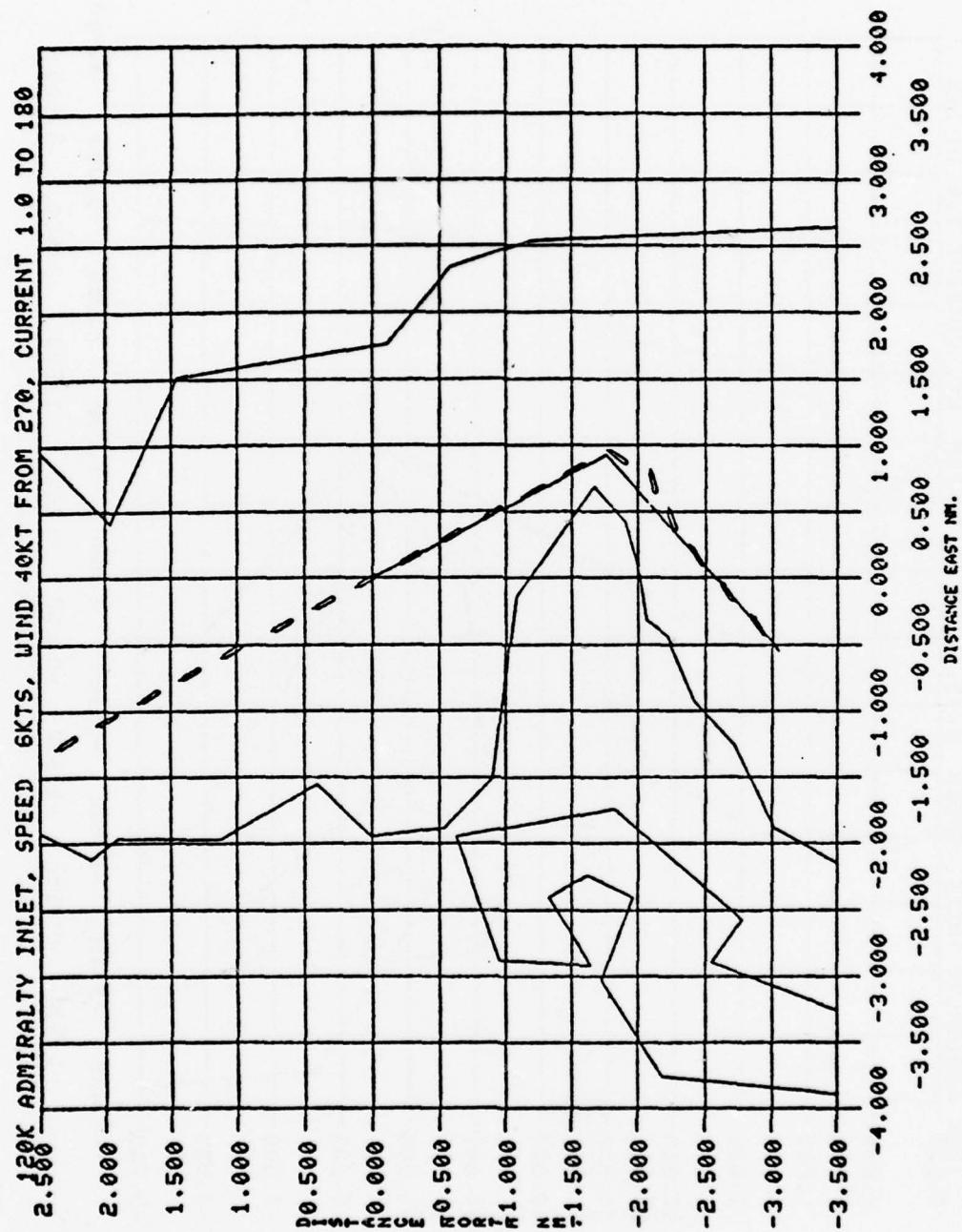
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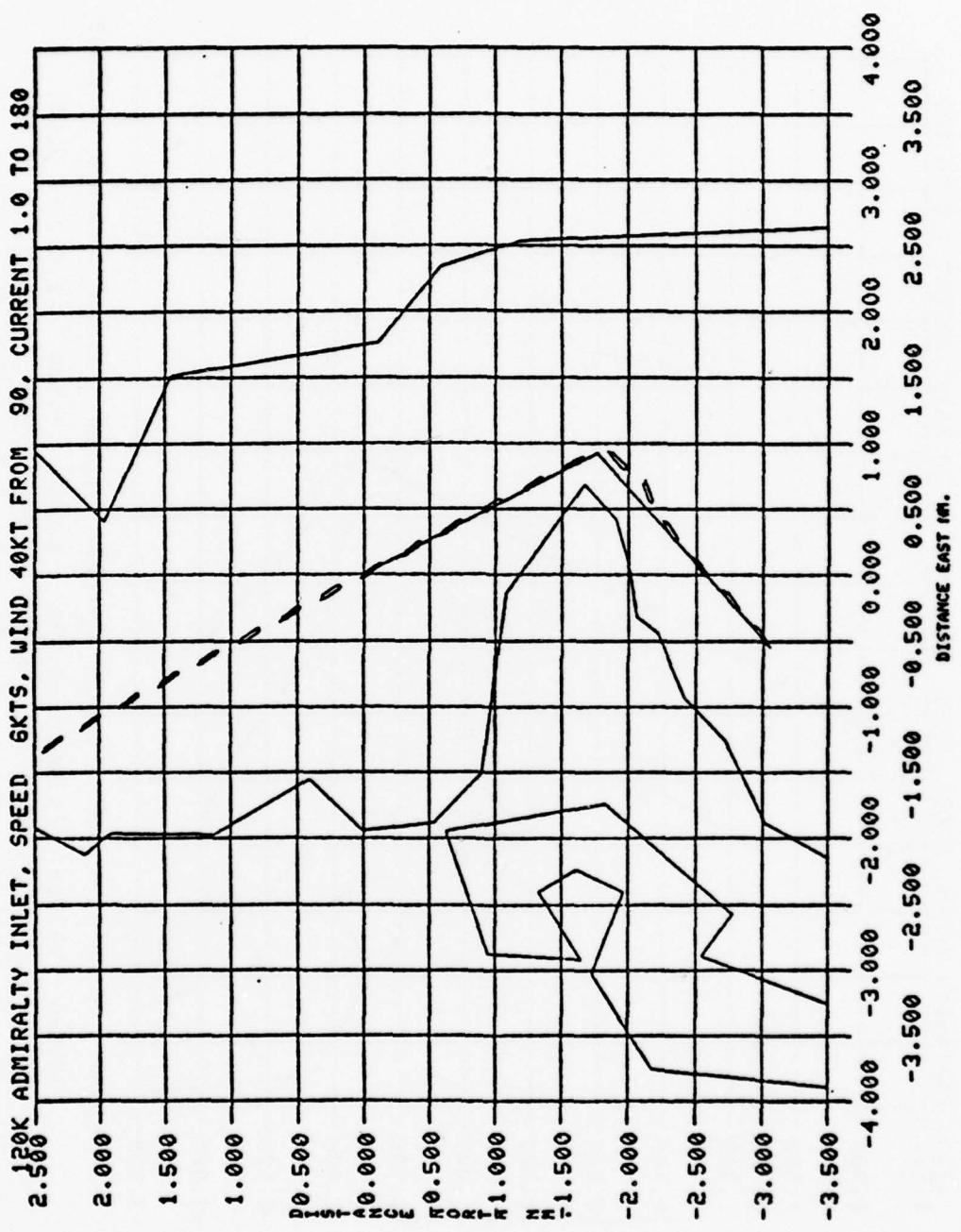
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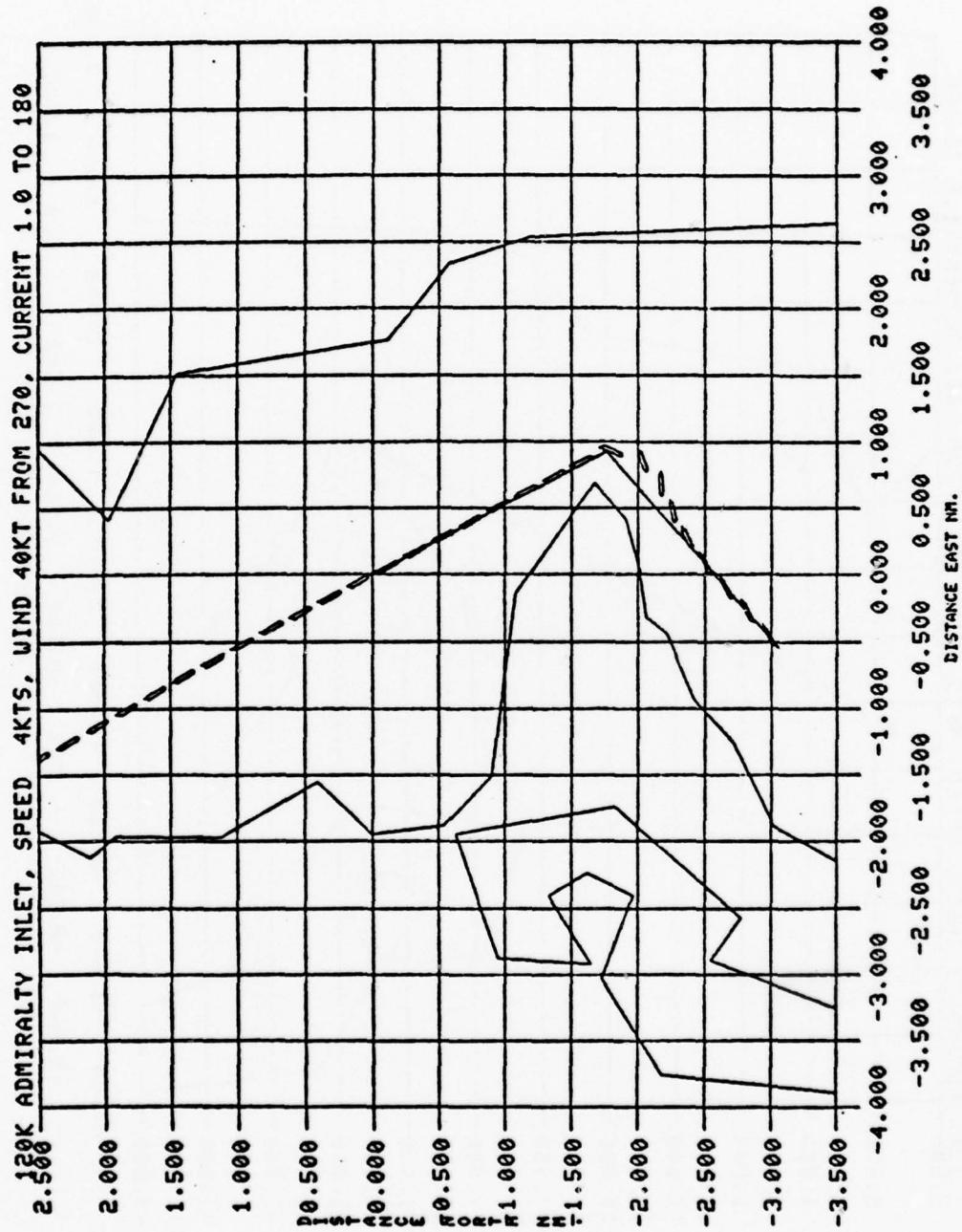
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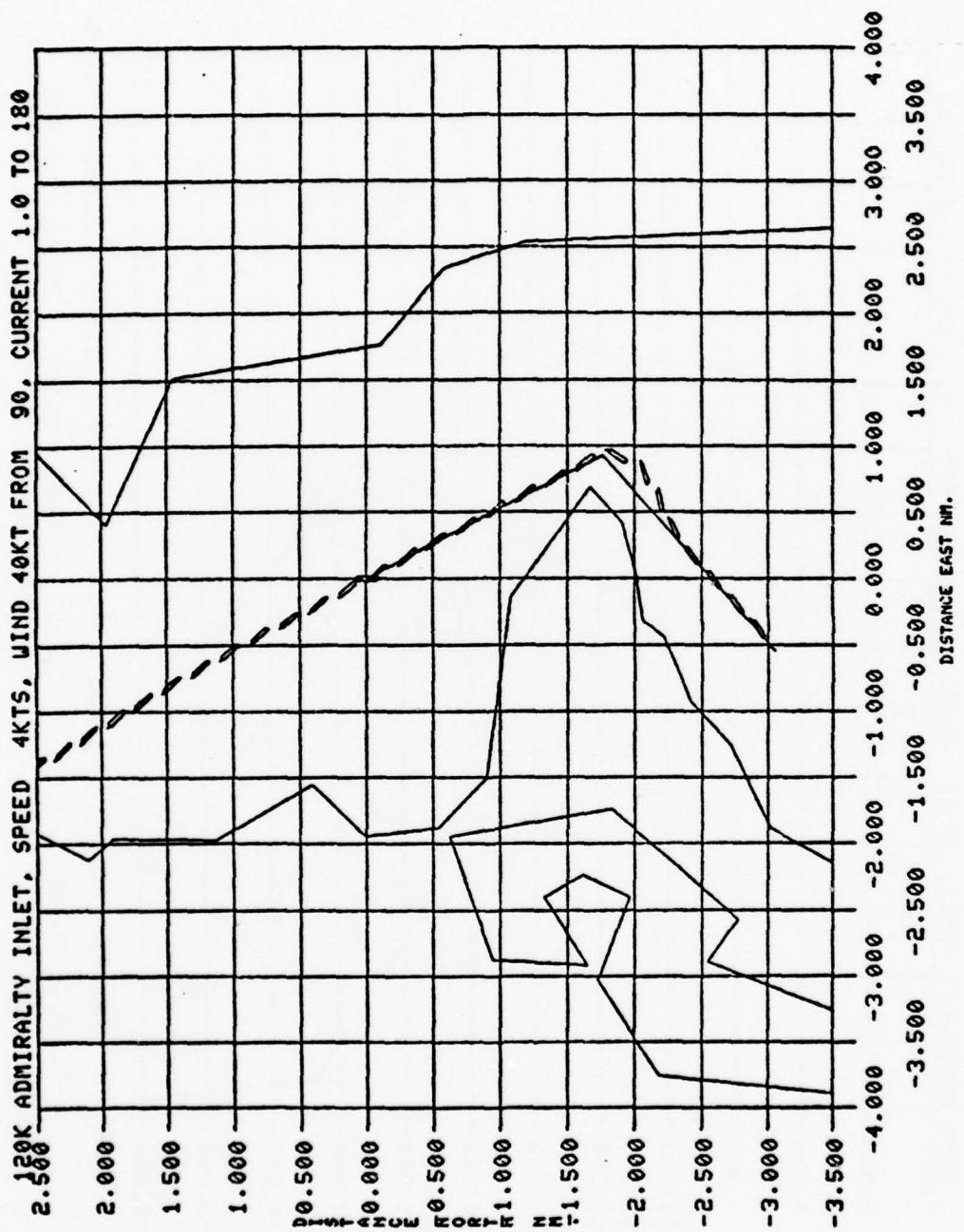
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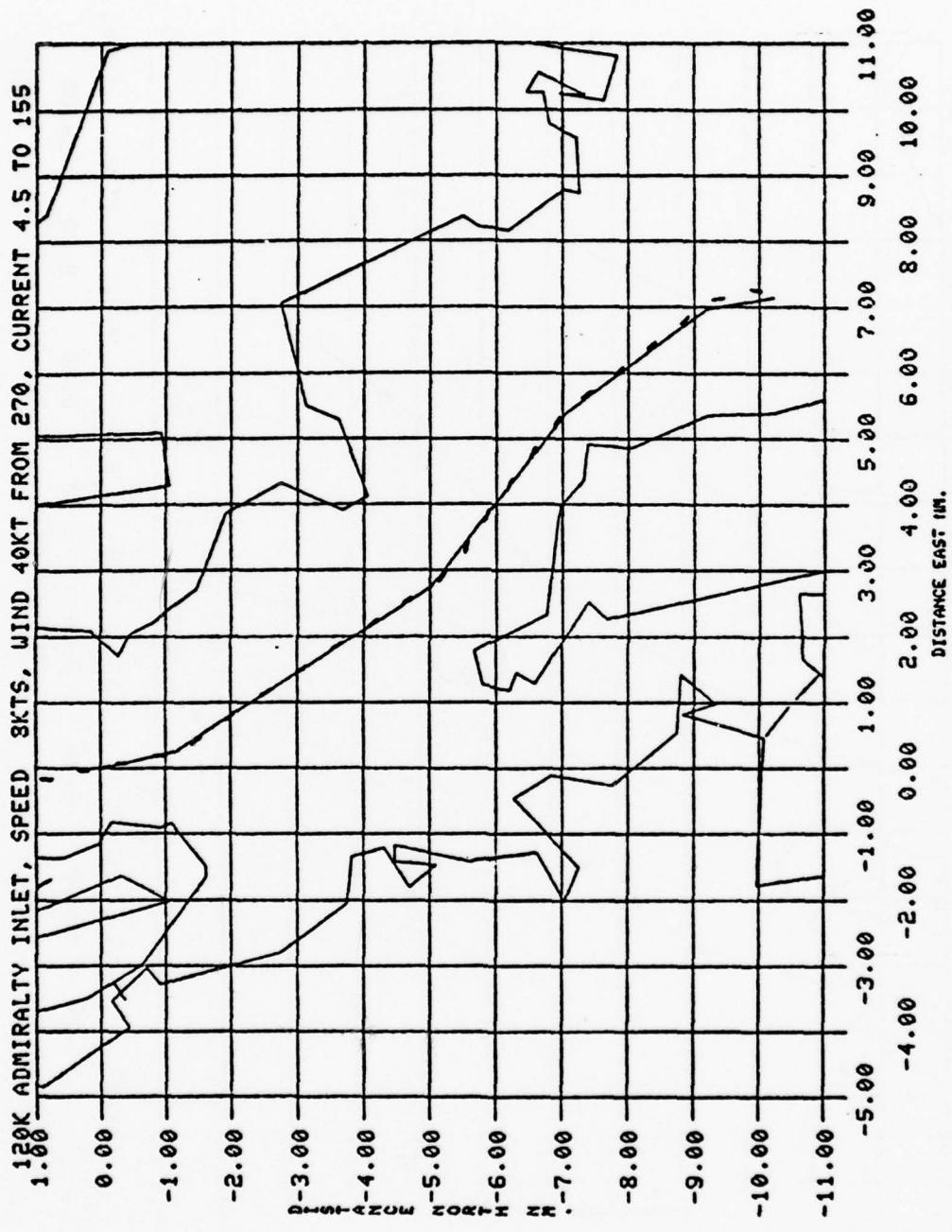


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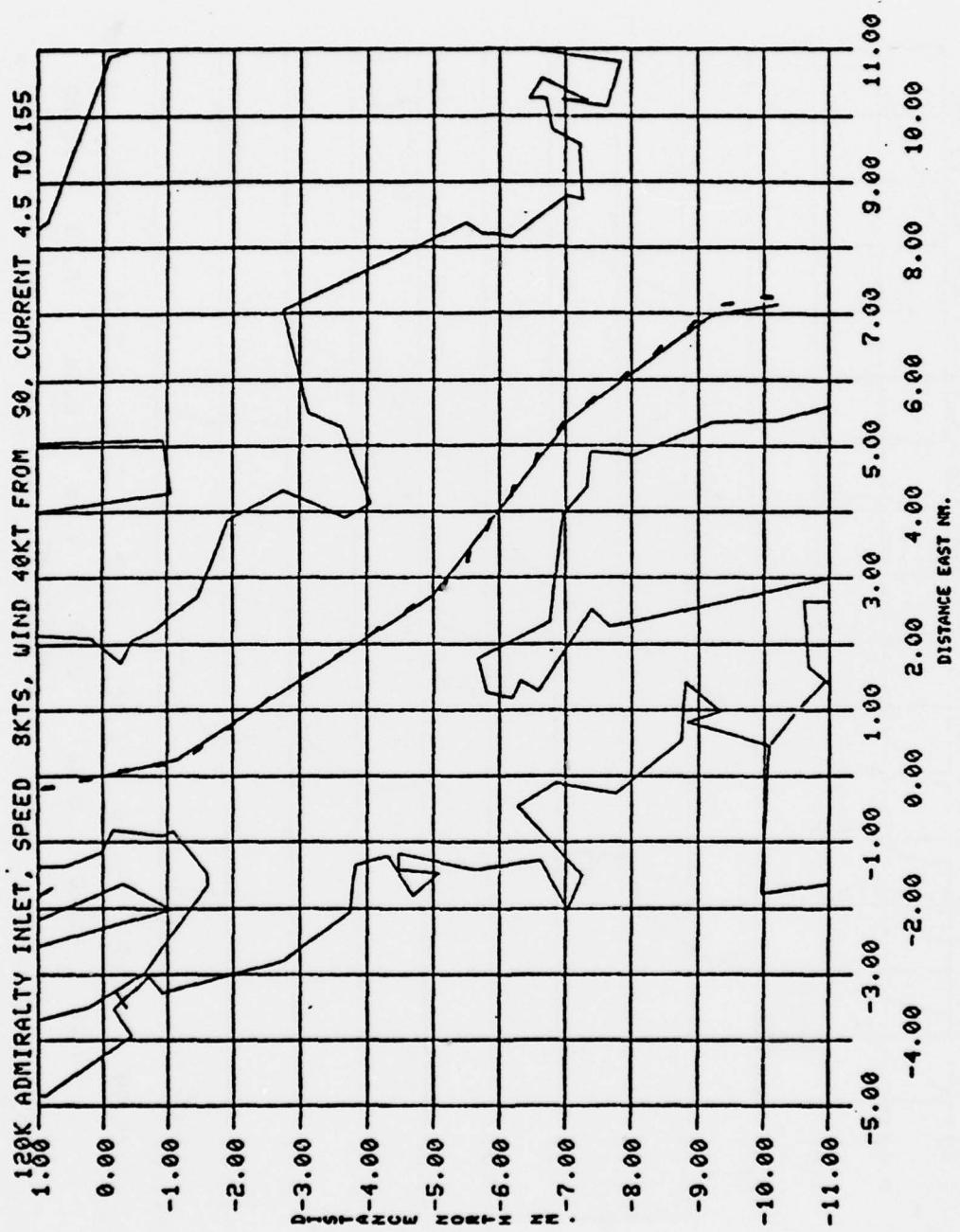


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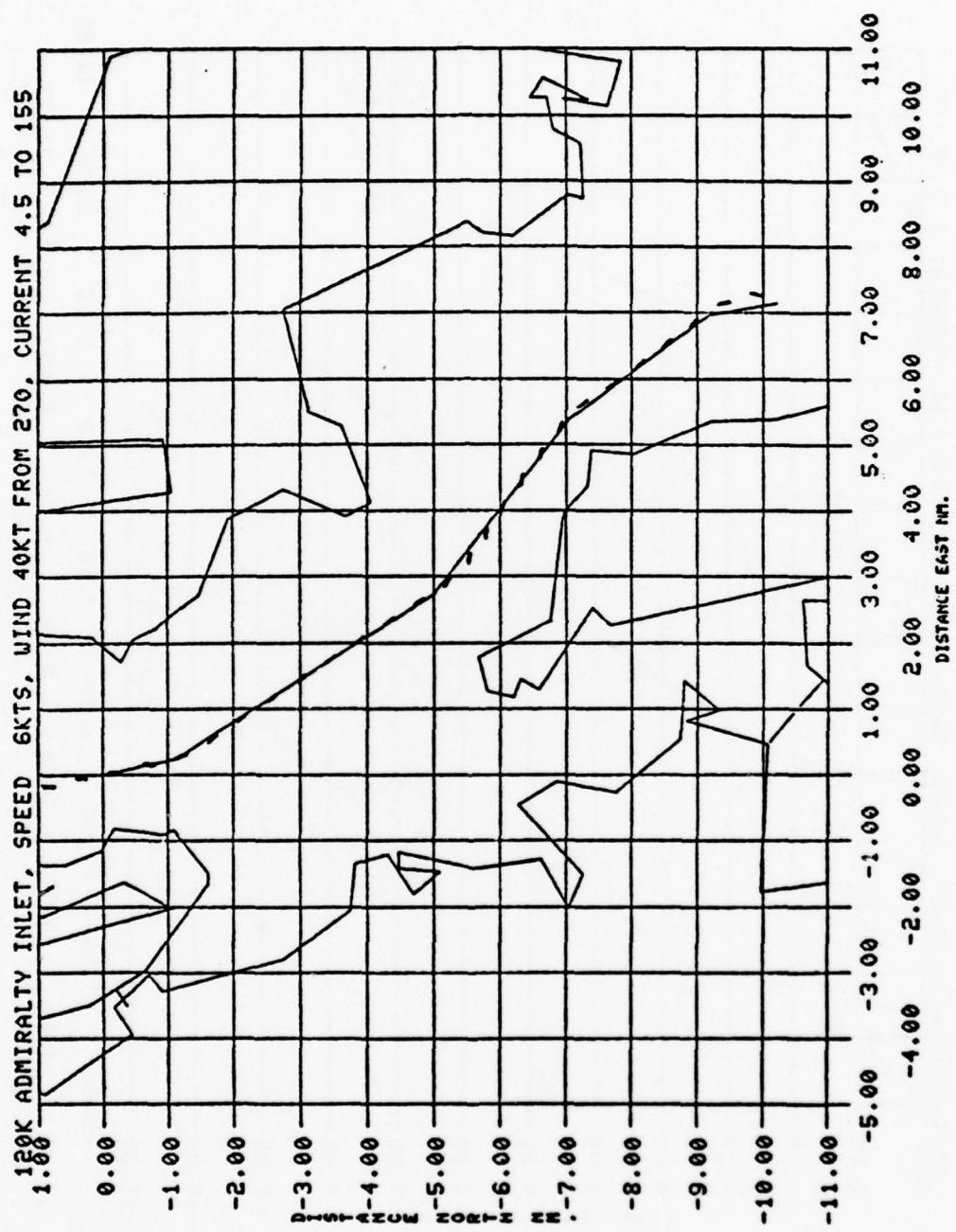




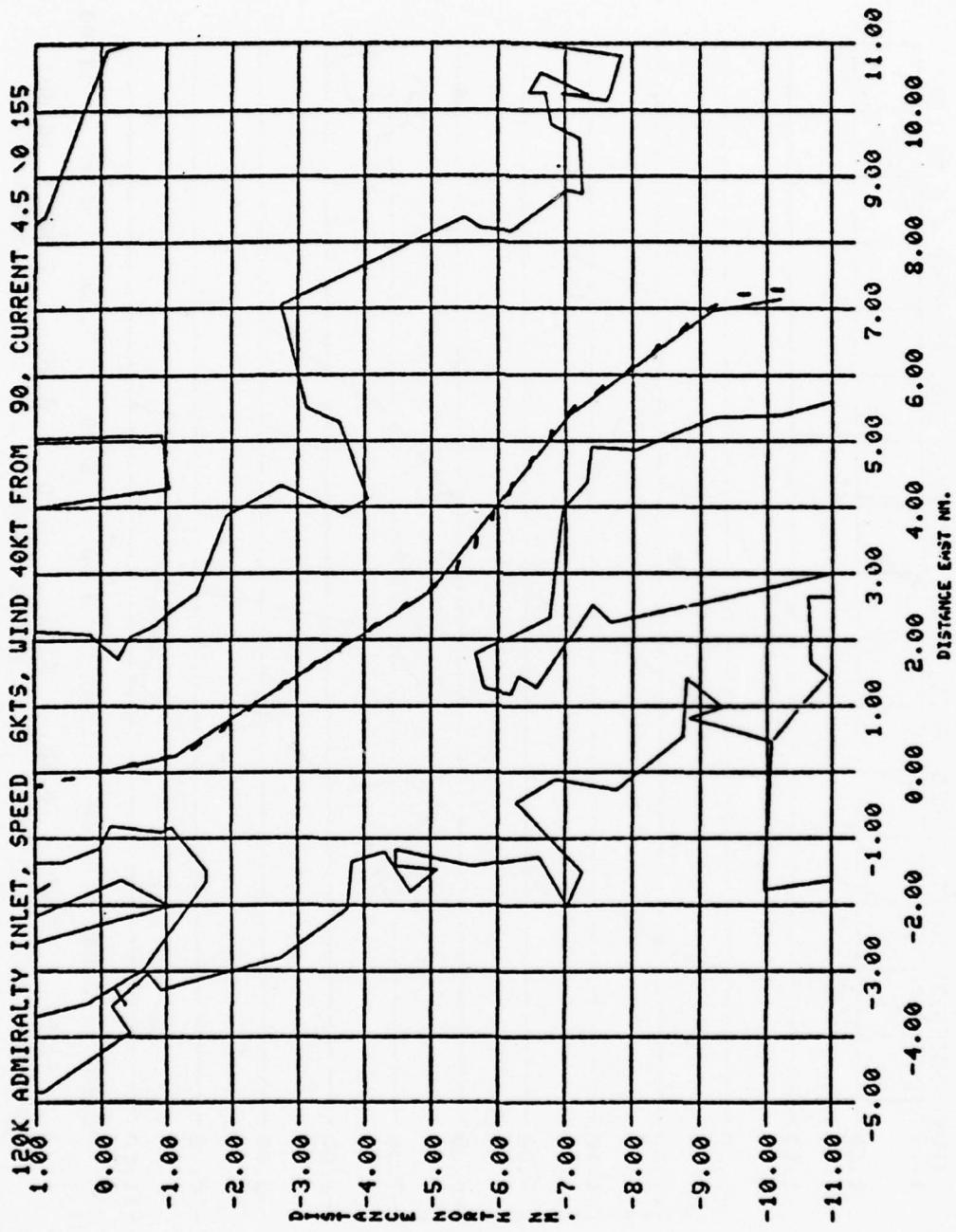
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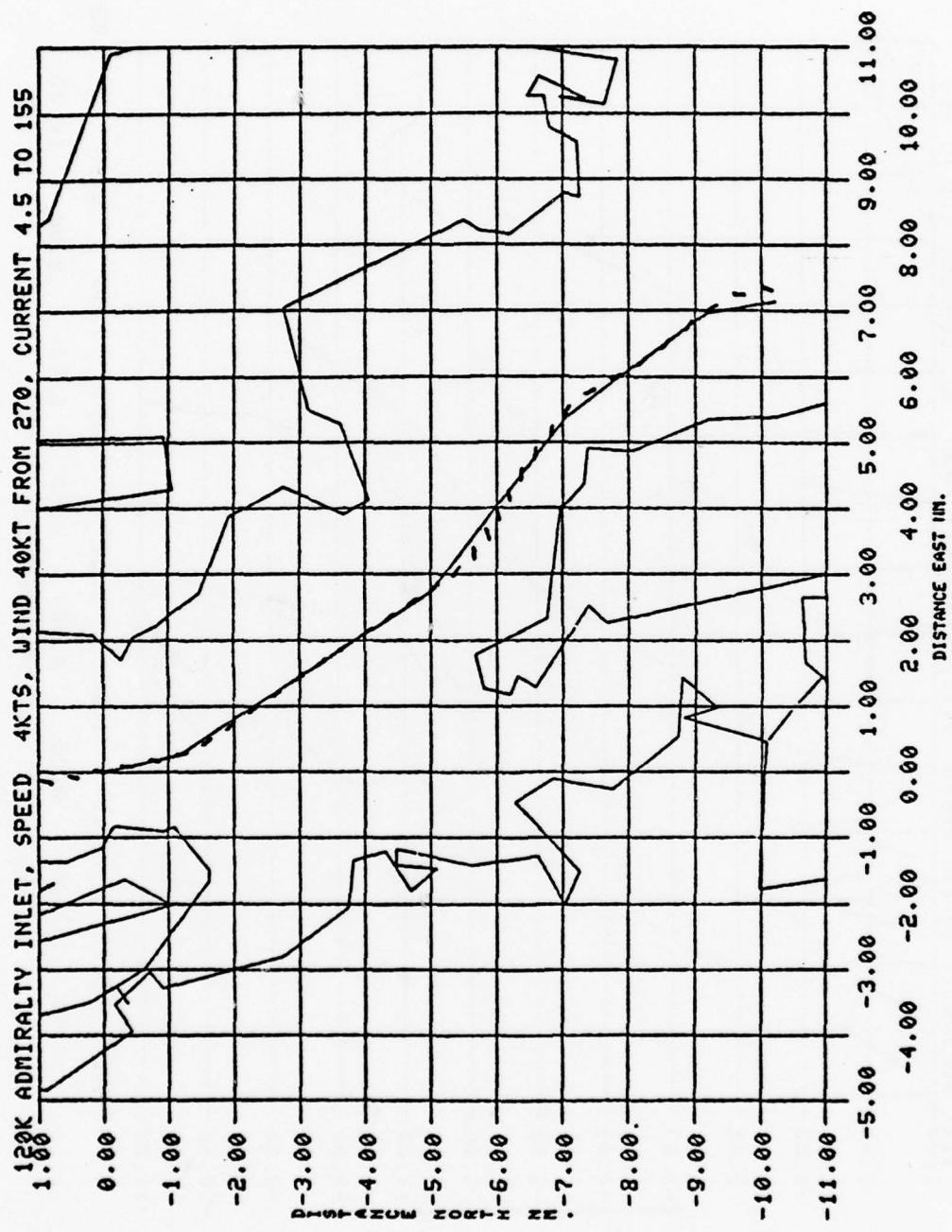
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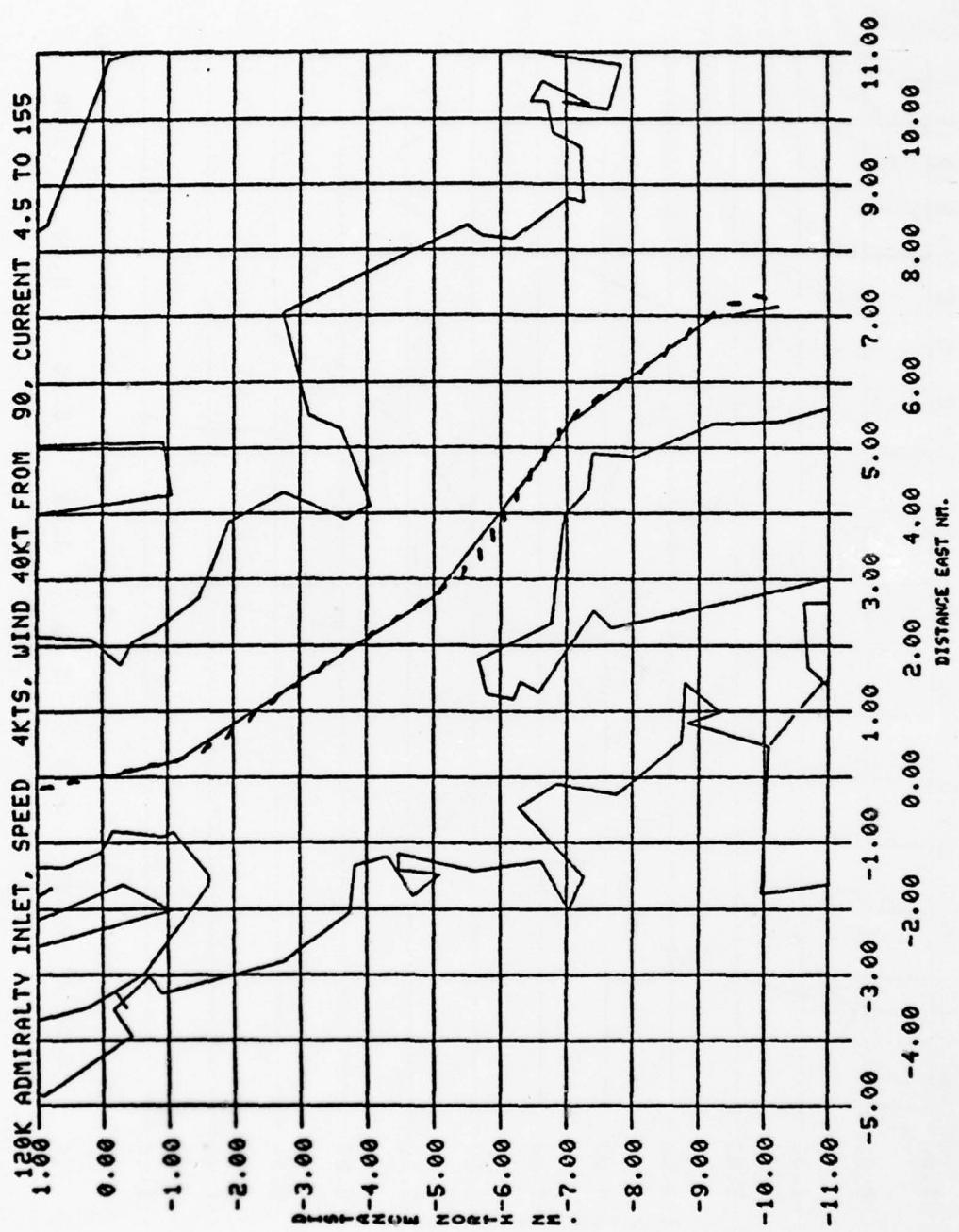
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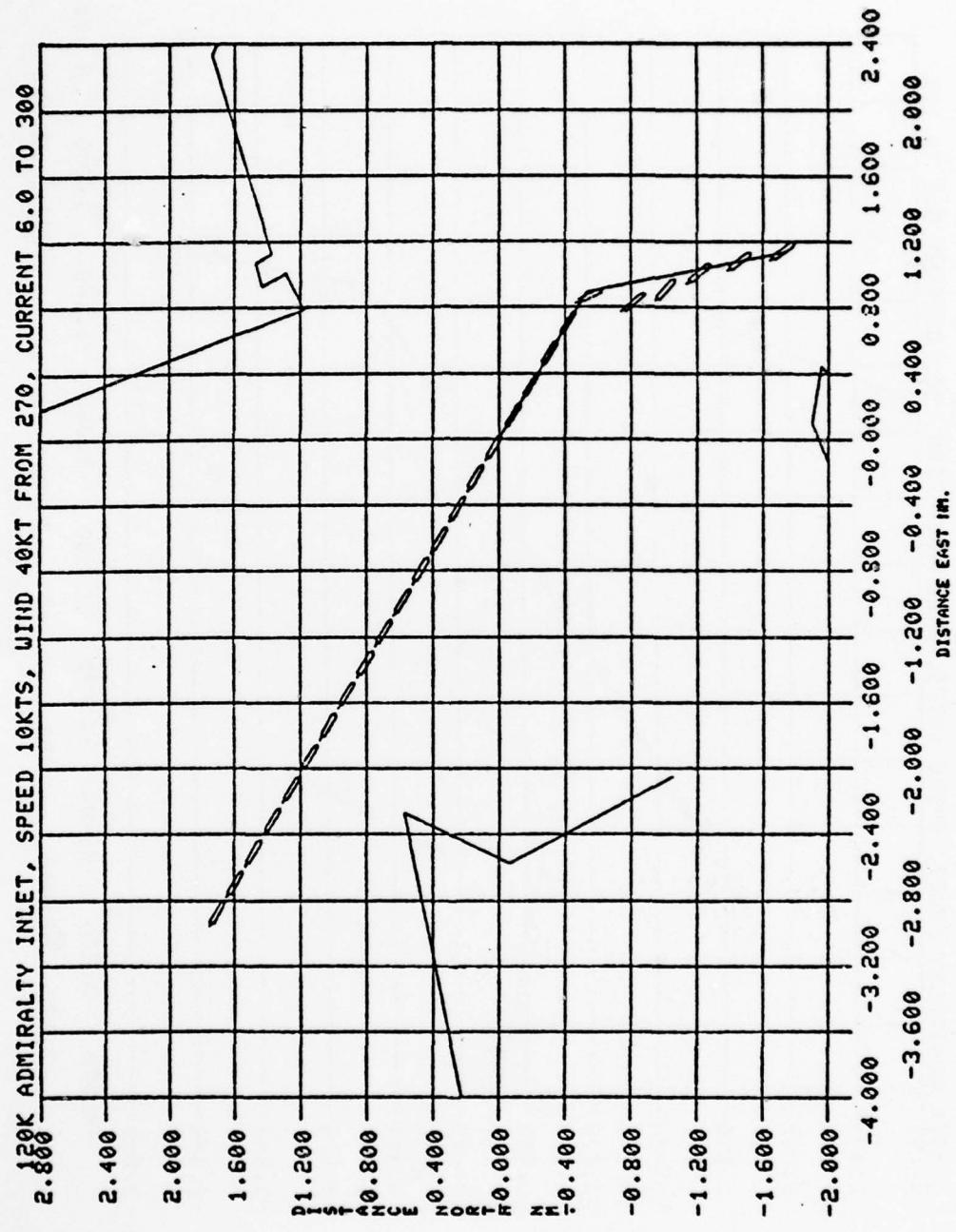
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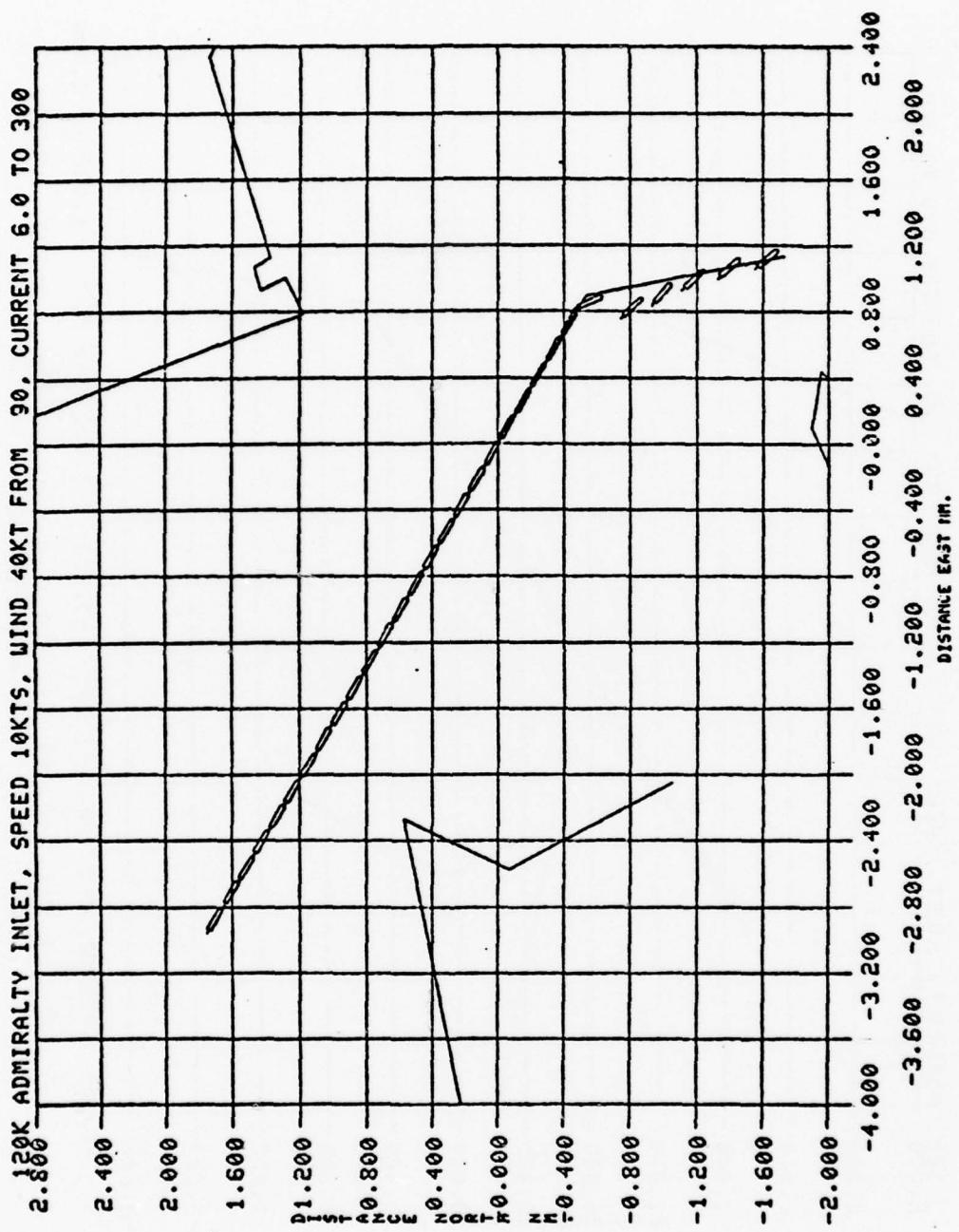
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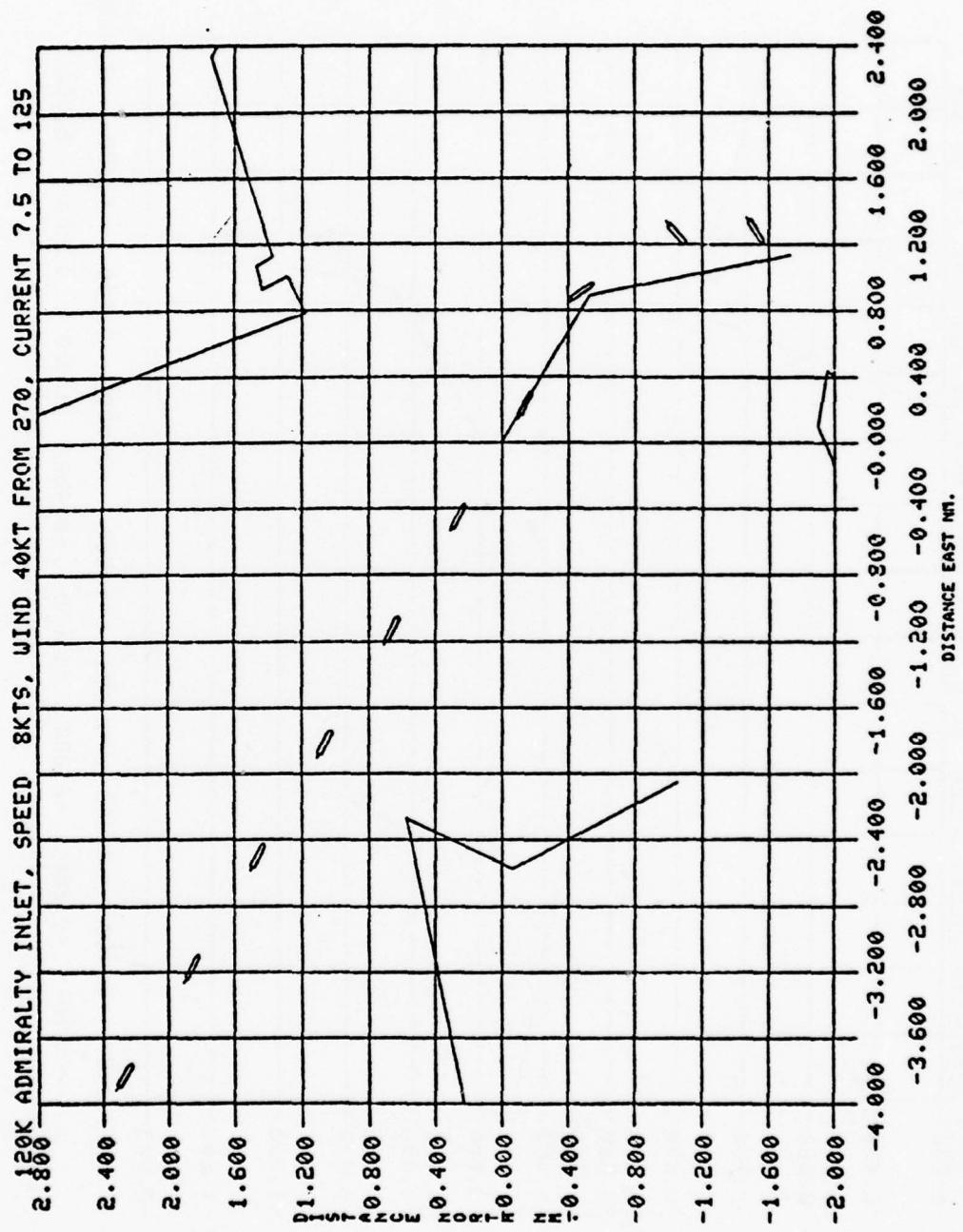
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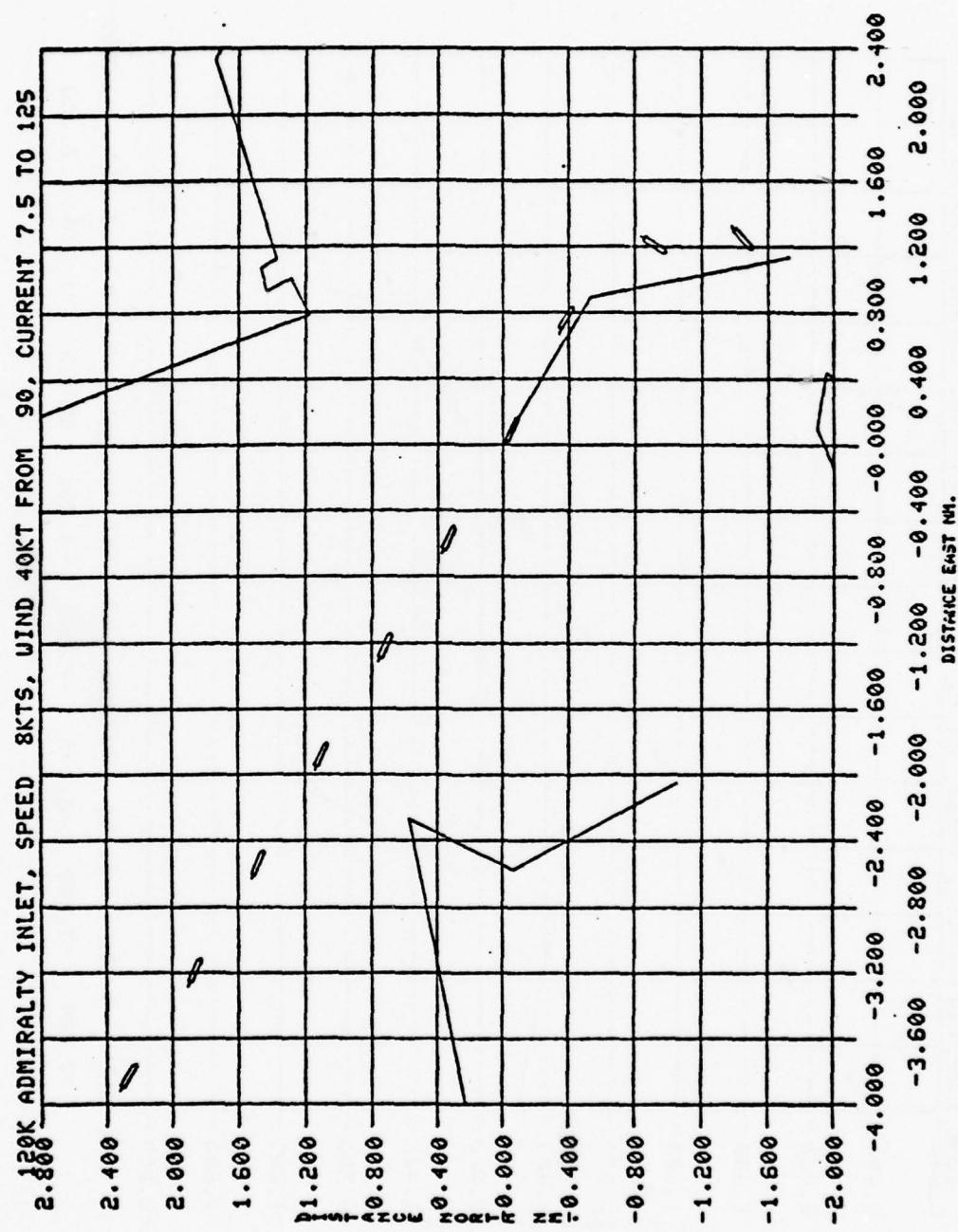


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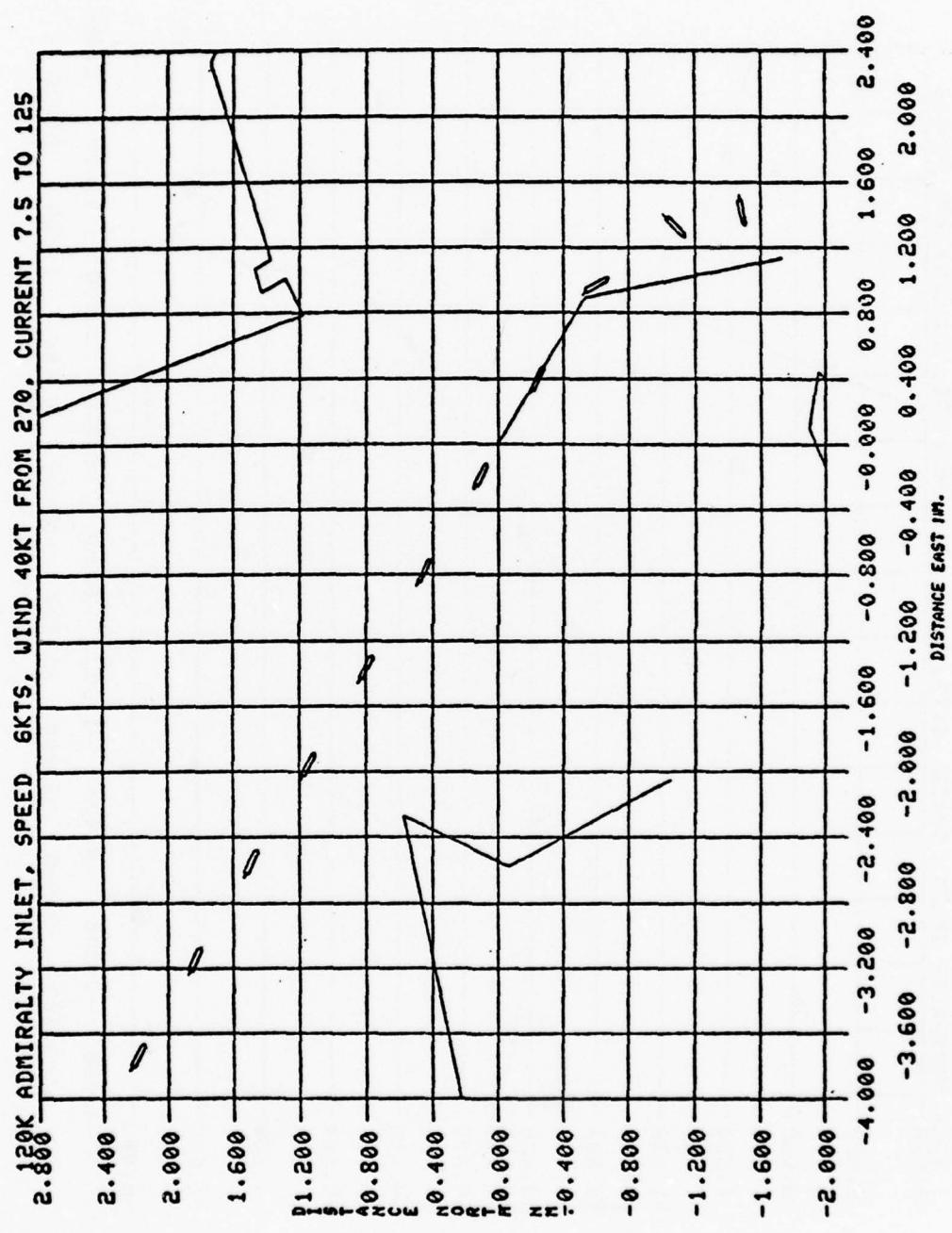


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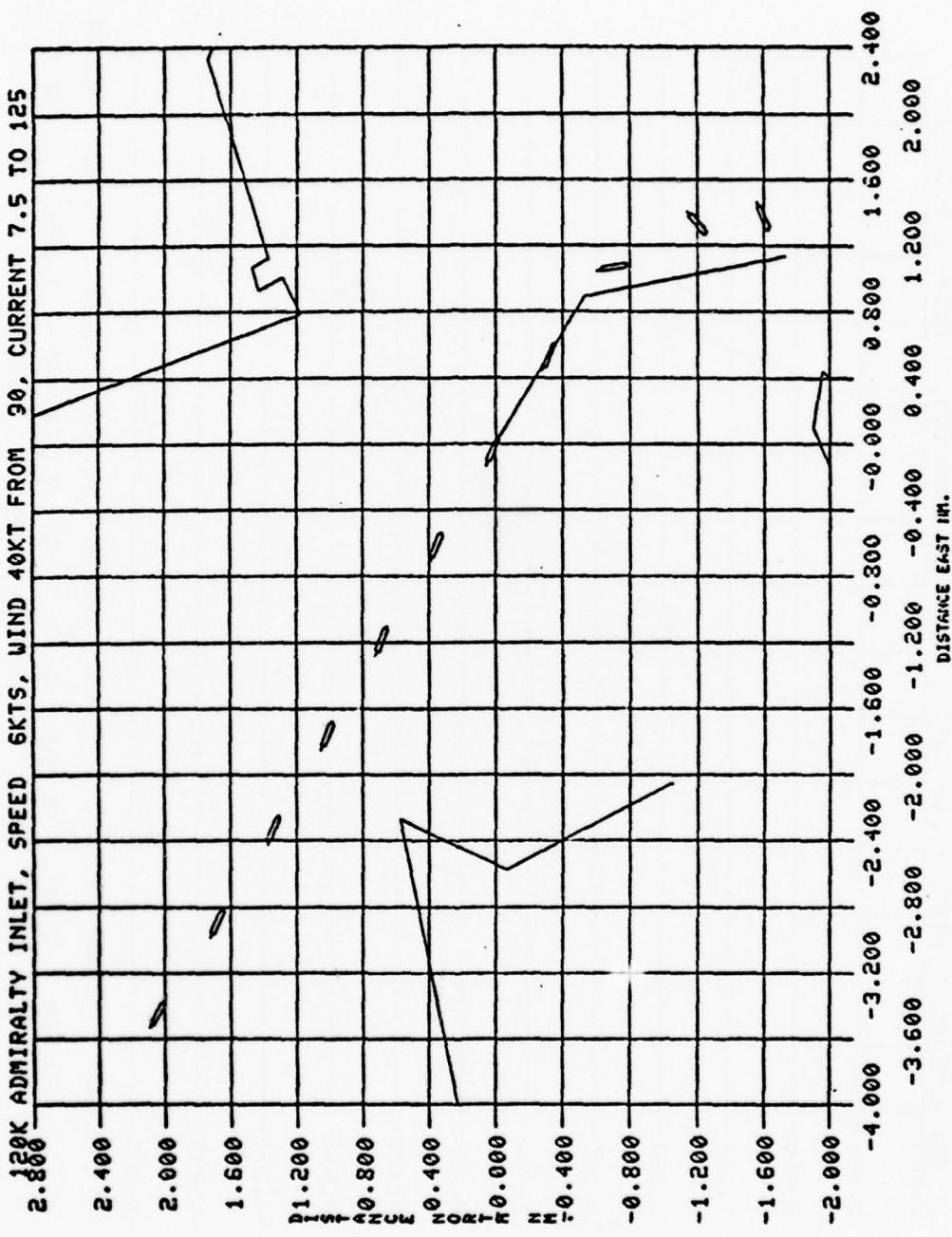




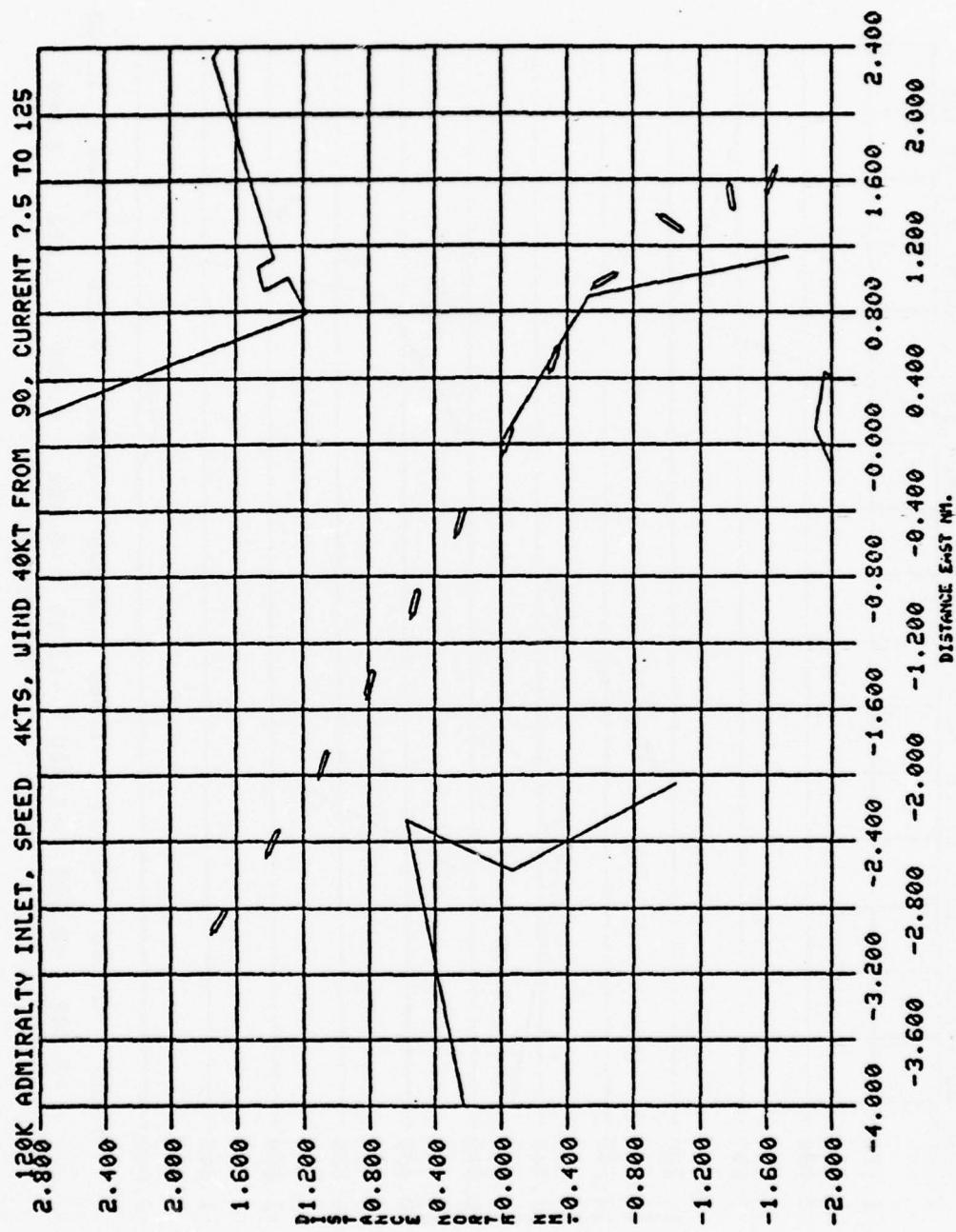
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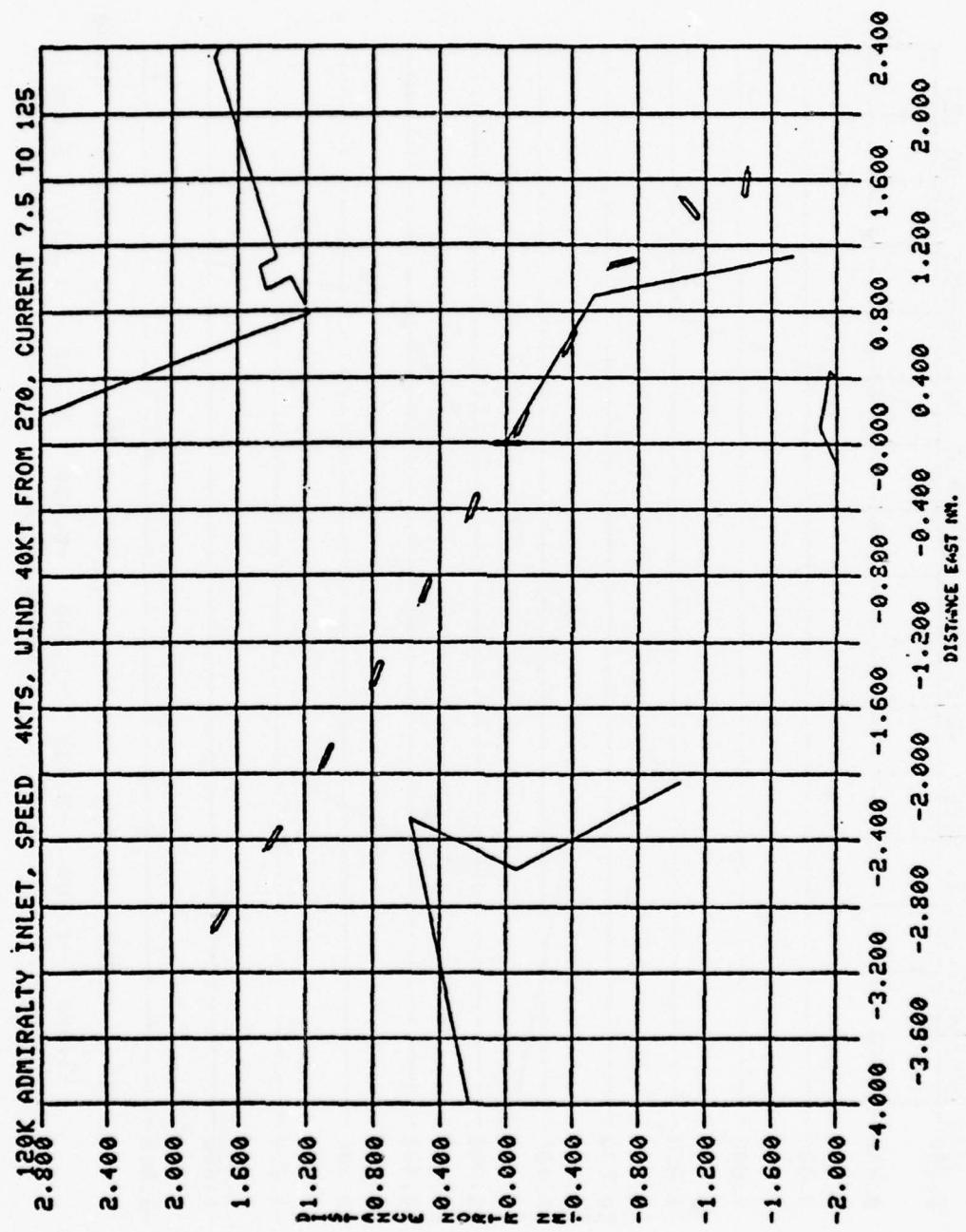
G-145



G-146



G-147

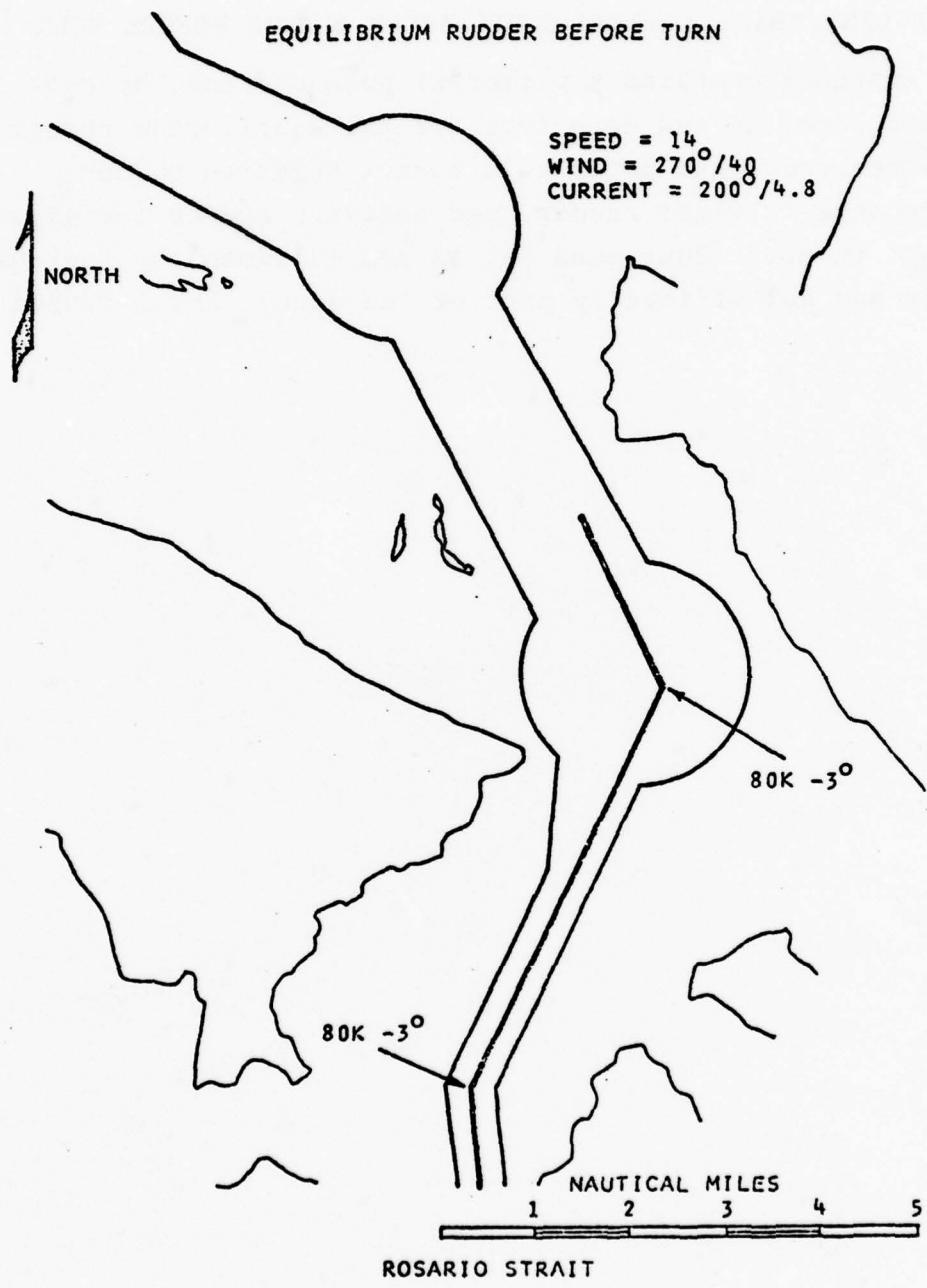


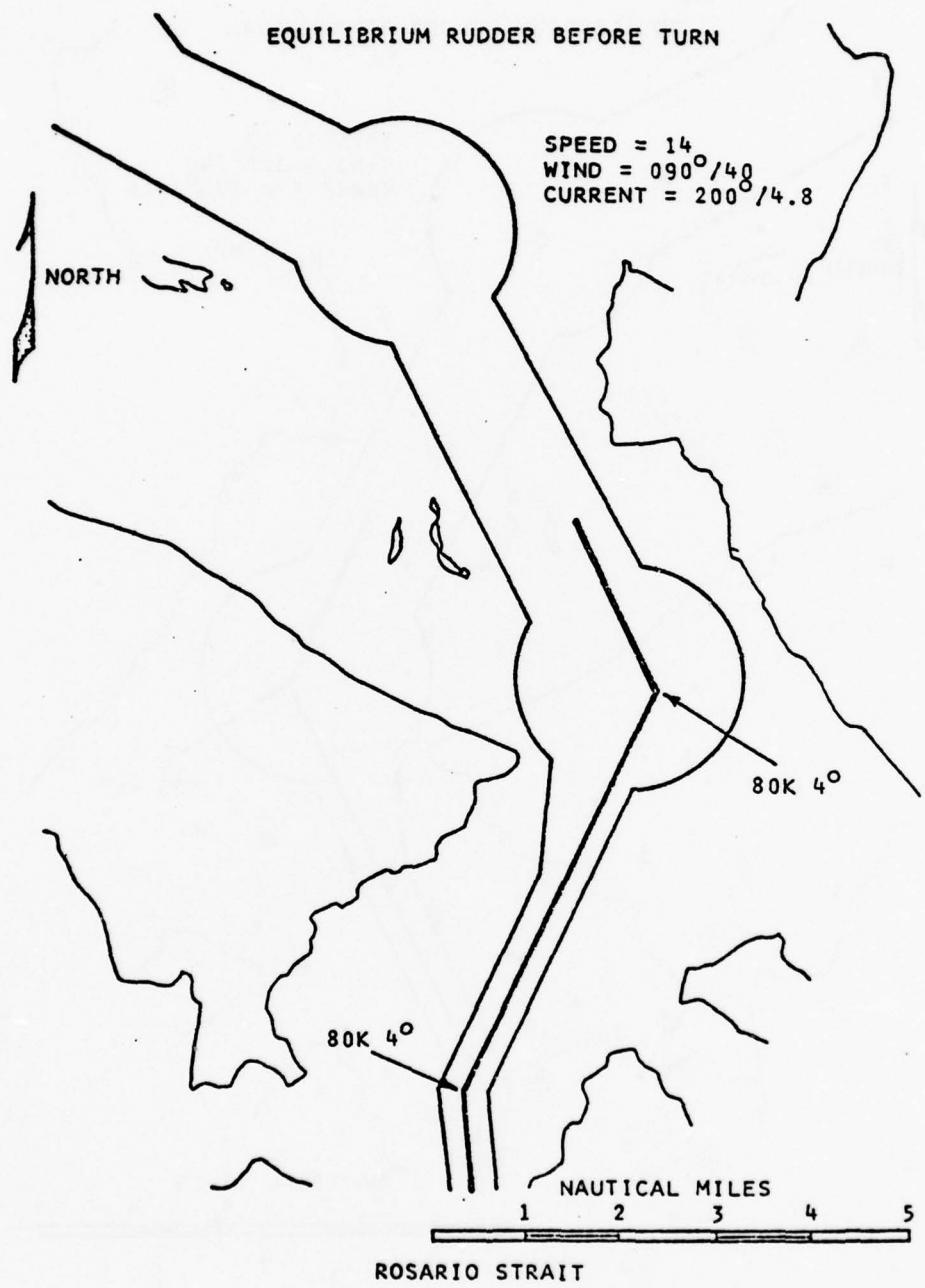
G-148

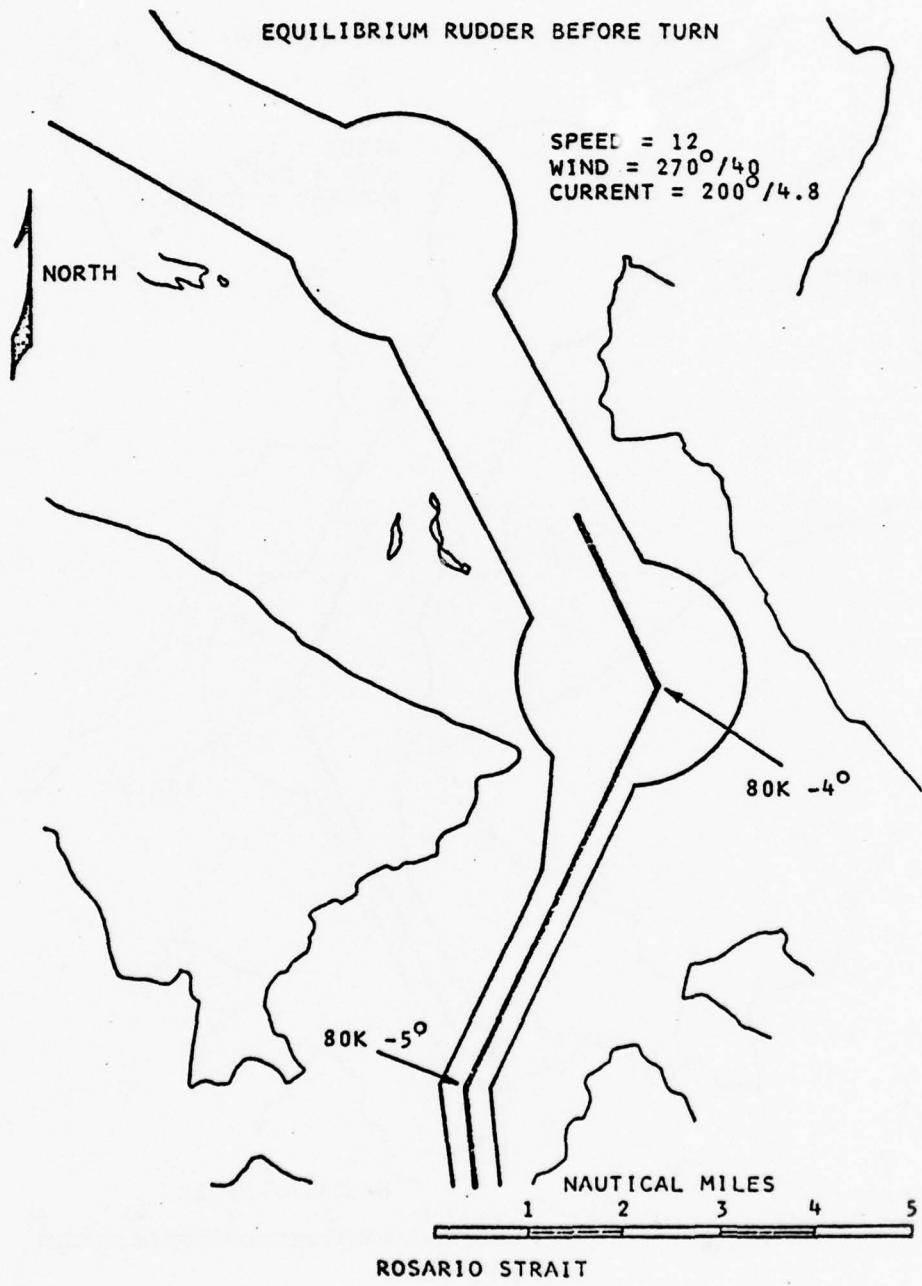
APPENDIX H

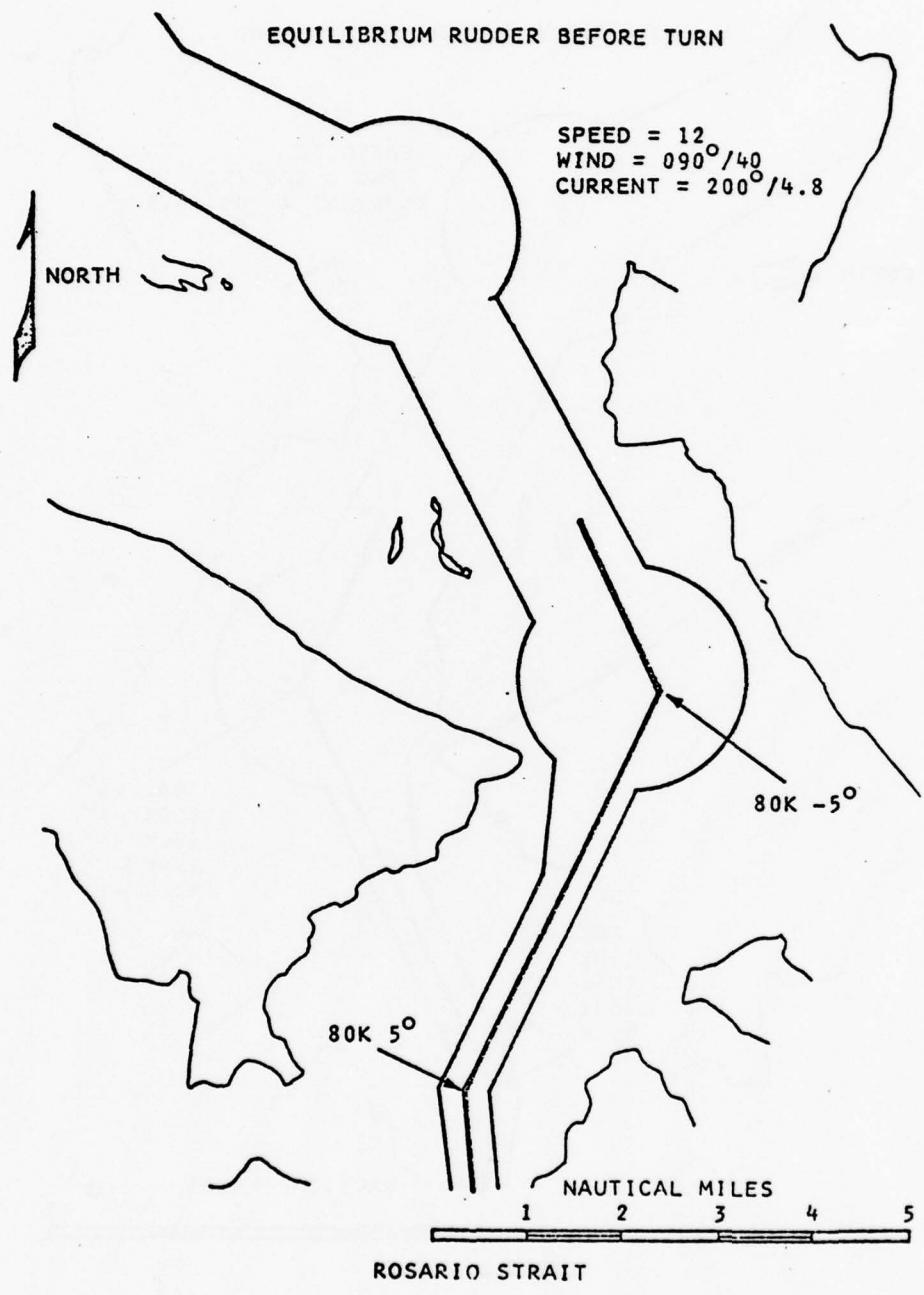
OFF-LINE TRACK KEEPING EQUILIBRIUM RUDDER BEFORE TURN

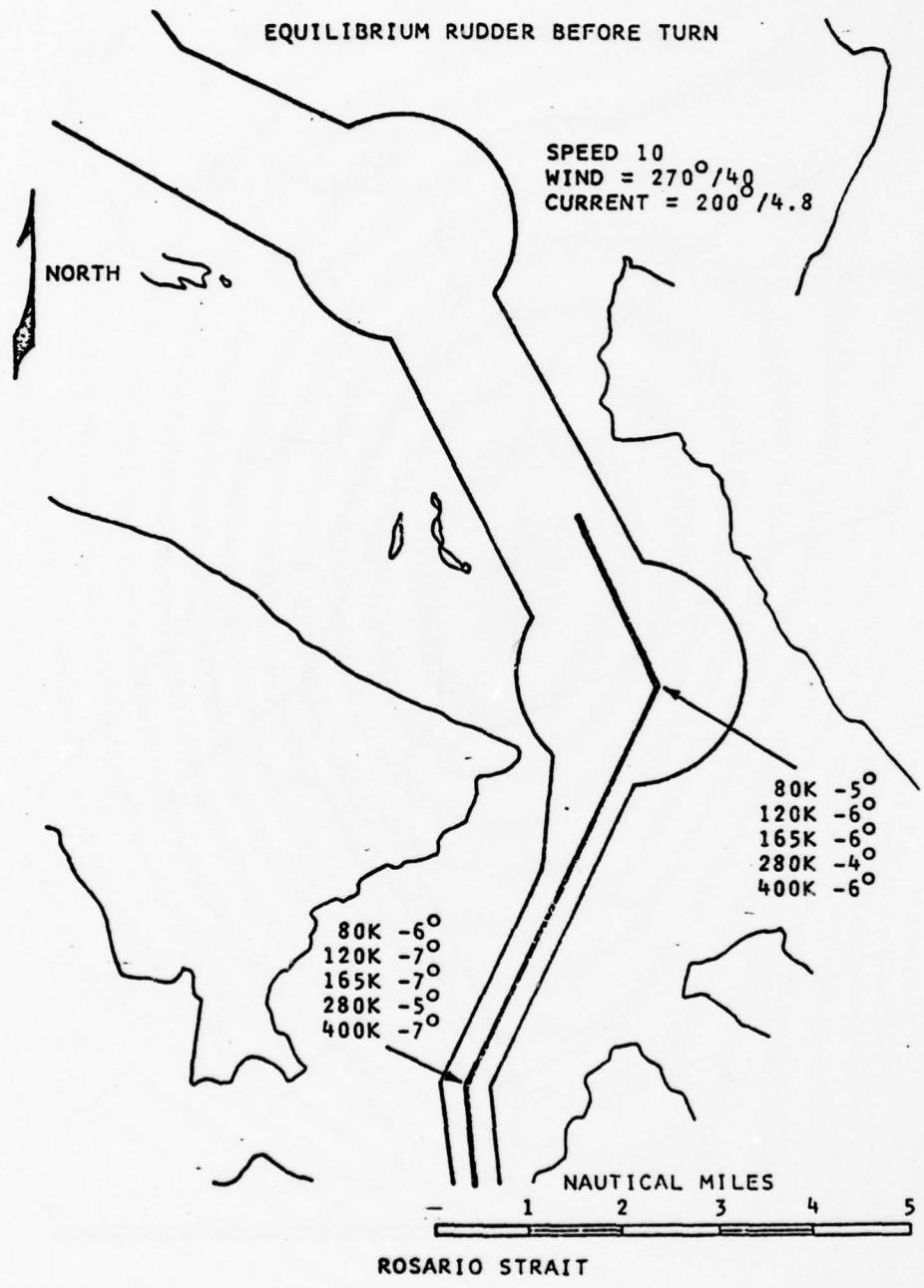
This appendix contains a pictorial presentation, by geographic location and ship type, of the equilibrium rudder angle required just prior to a turn. Negative rudder corresponds to right rudder, and positive rudder corresponds to left rudder. Four runs (at 12 and 14 knots) by the 80K tanker and not officially part of the study, are included.

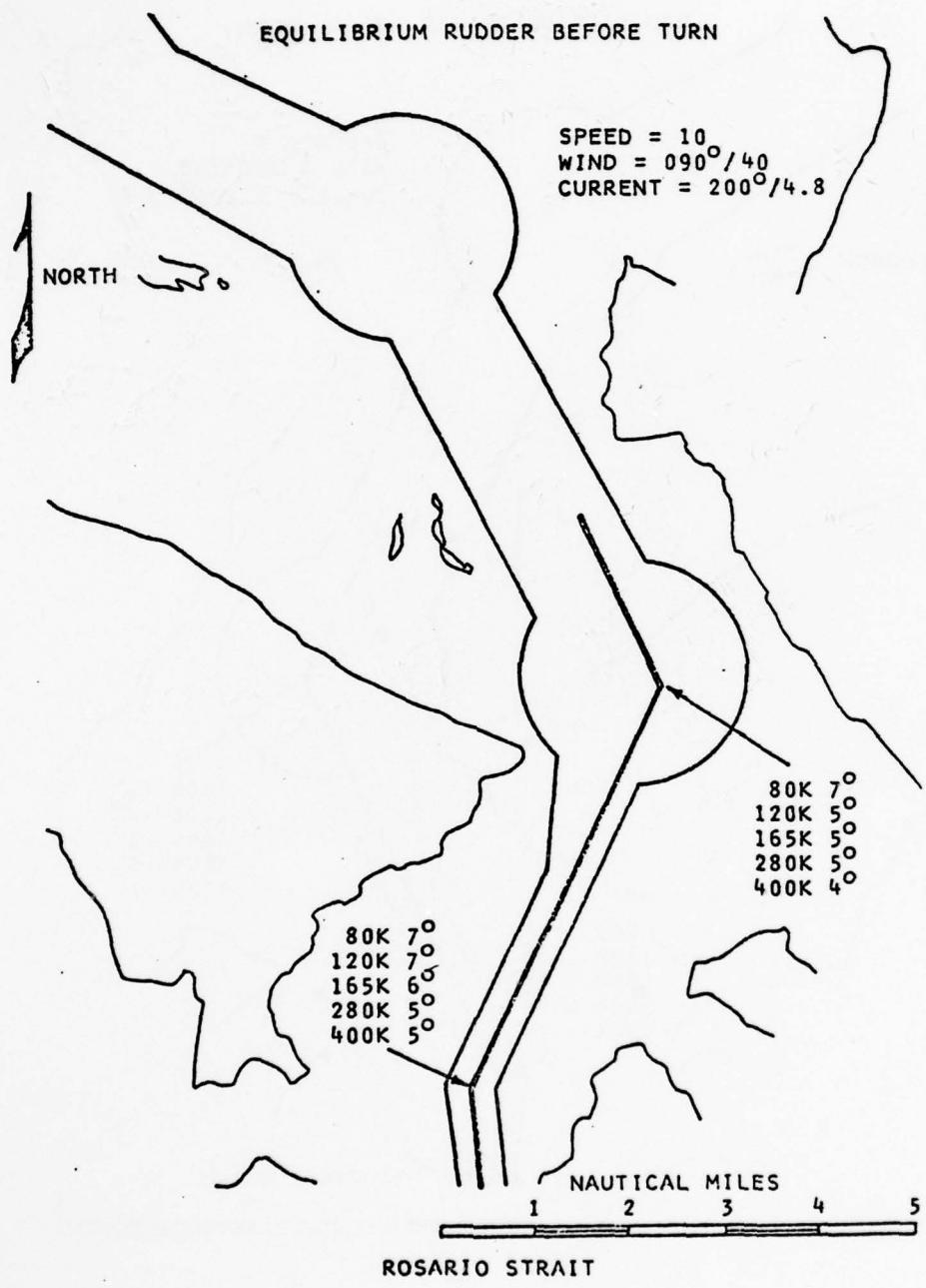


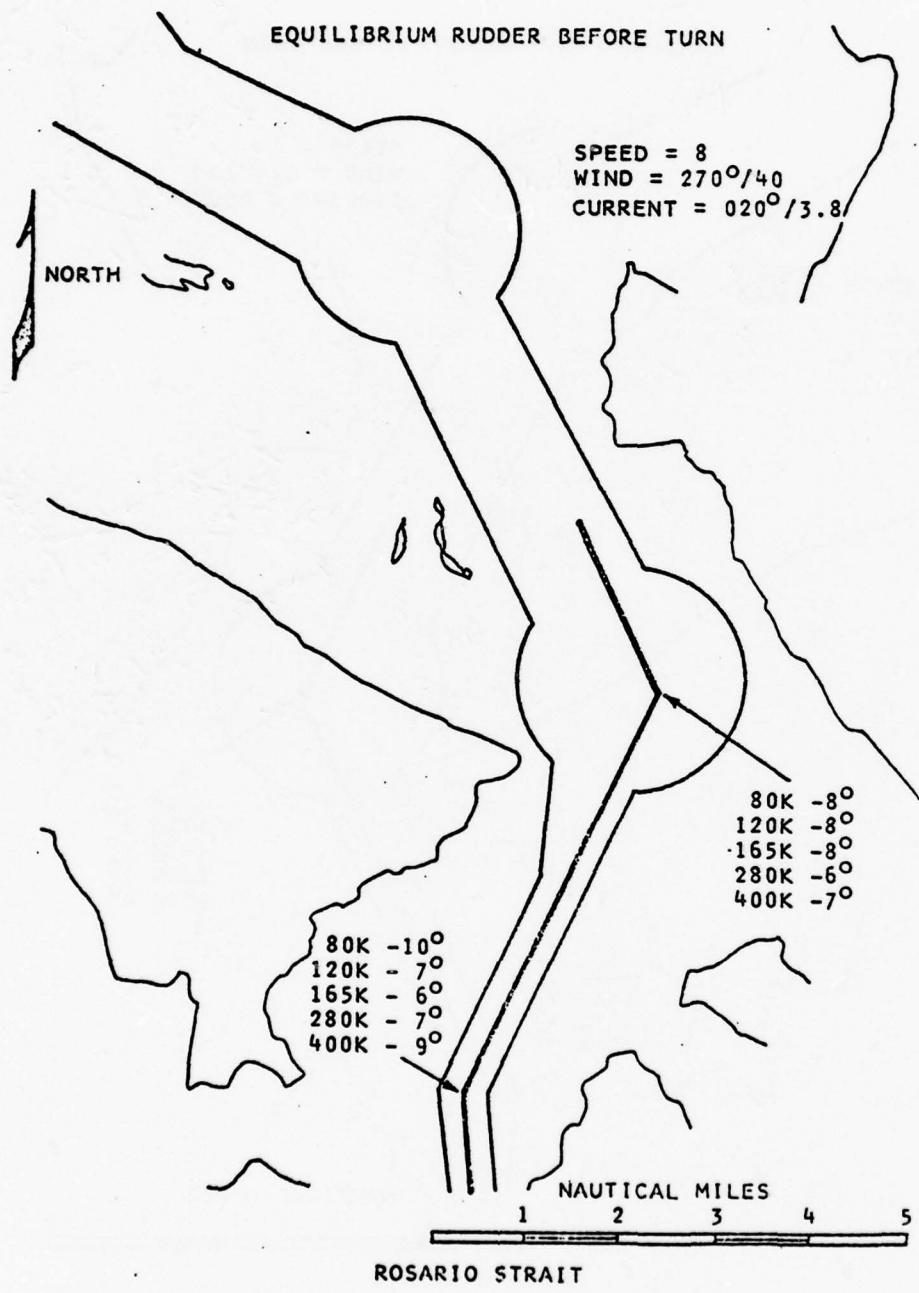


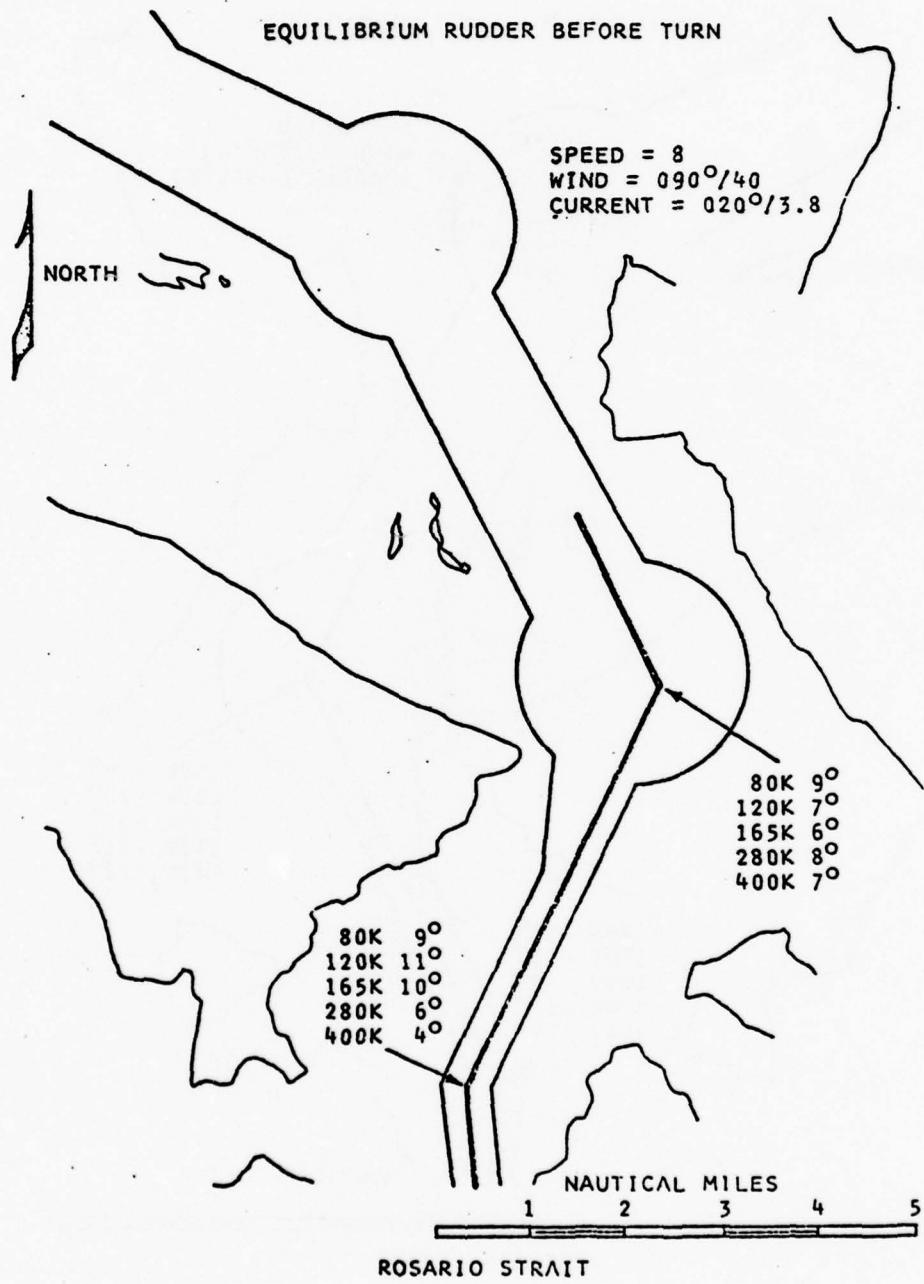


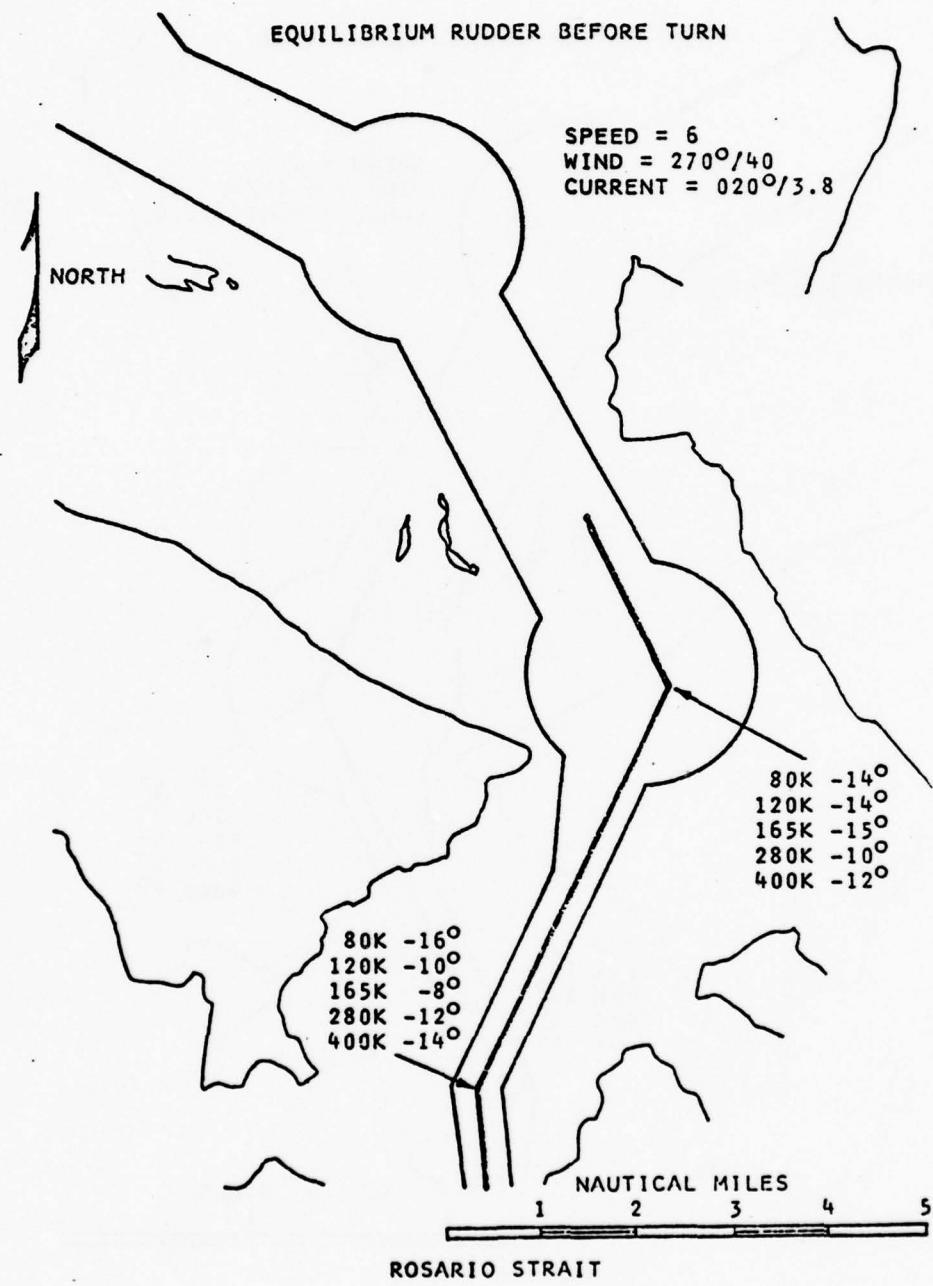


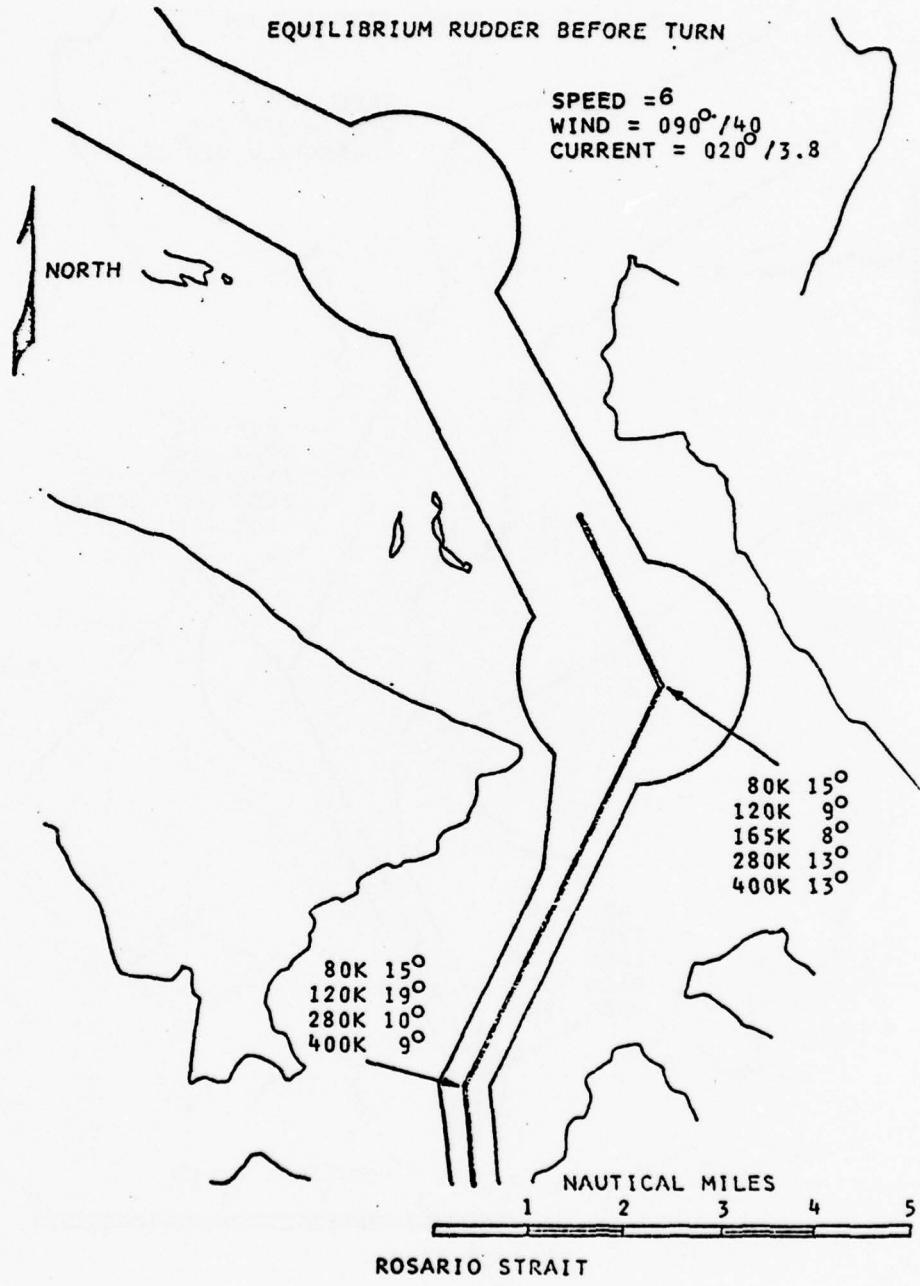


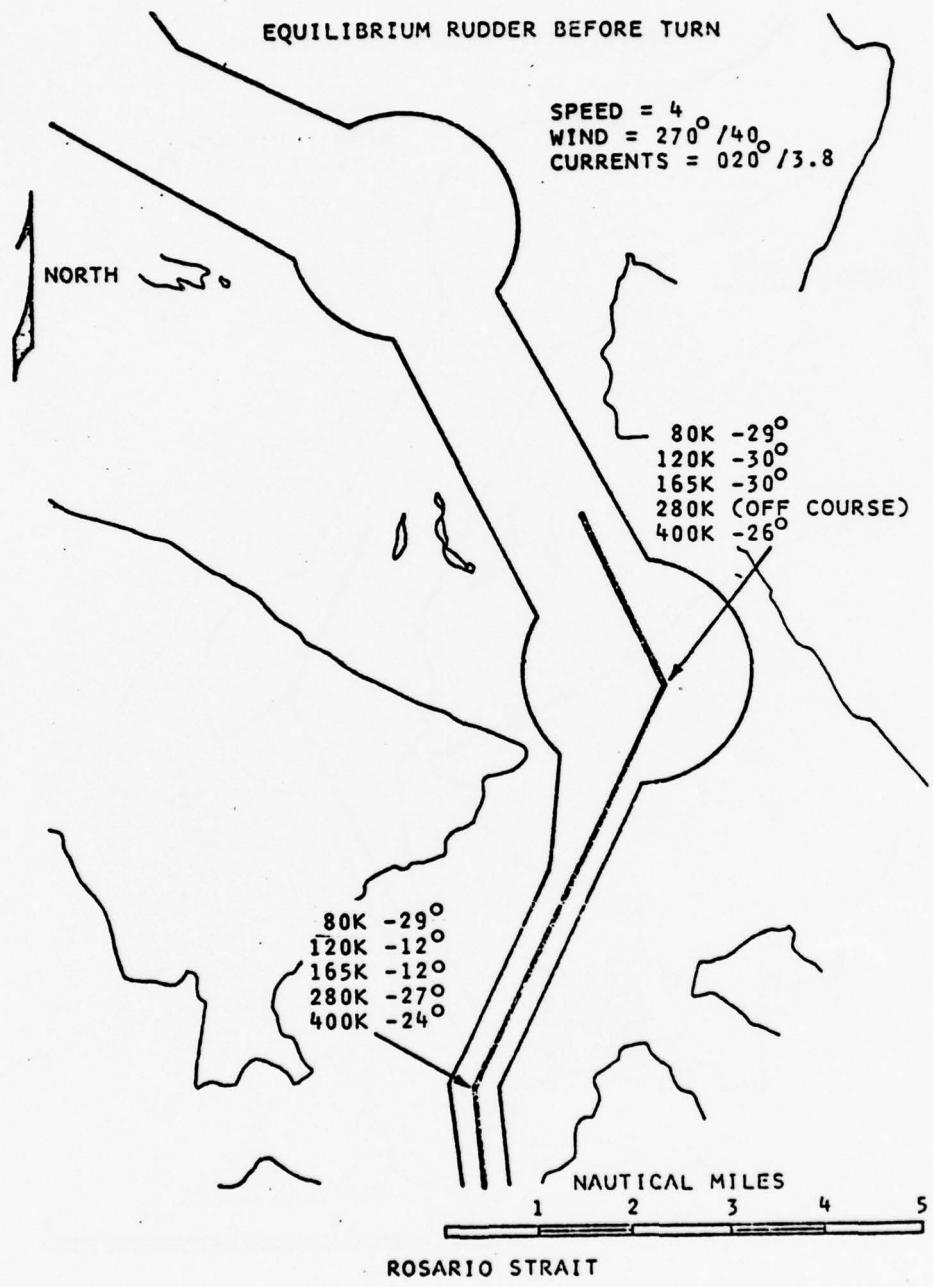


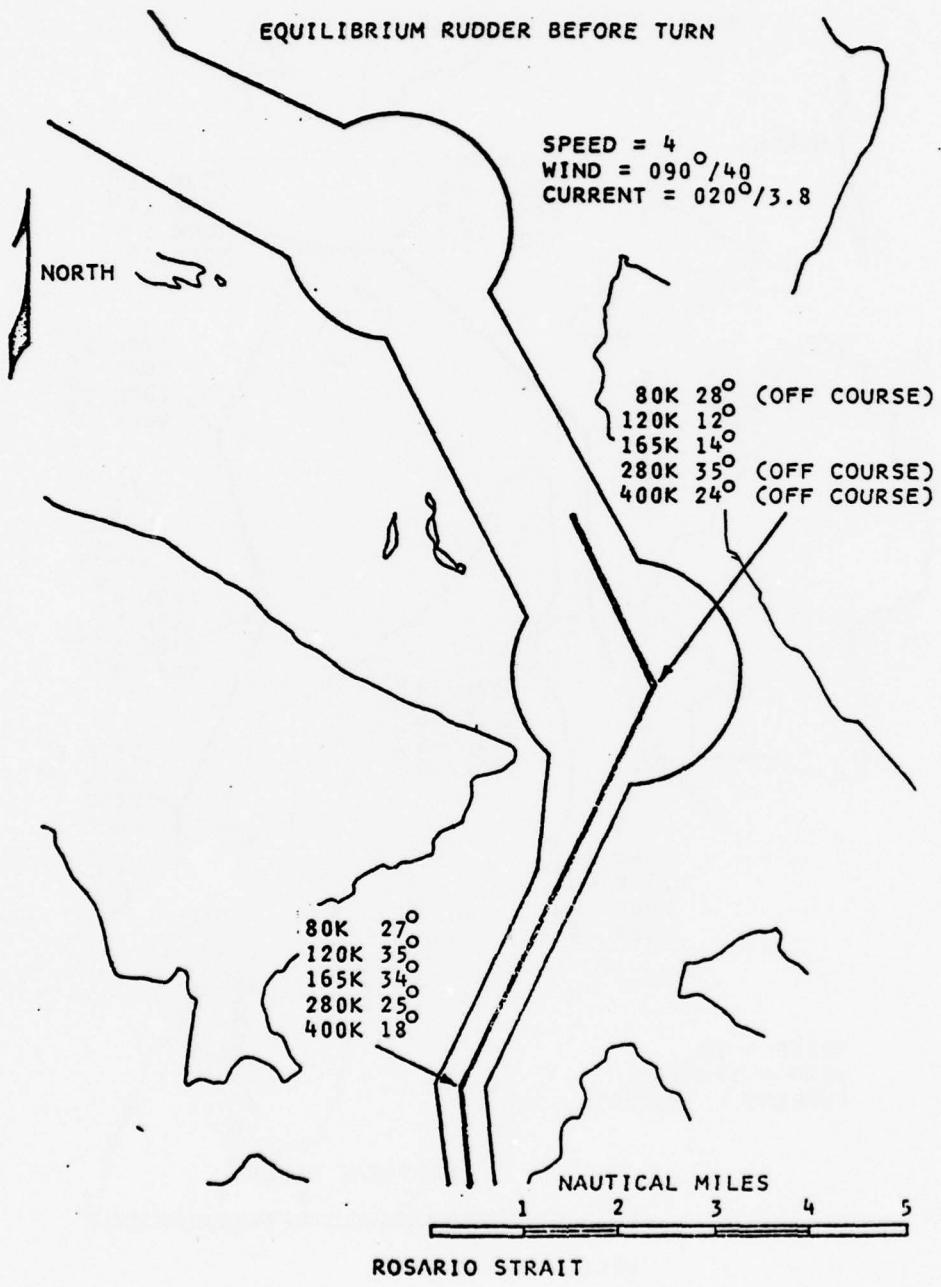


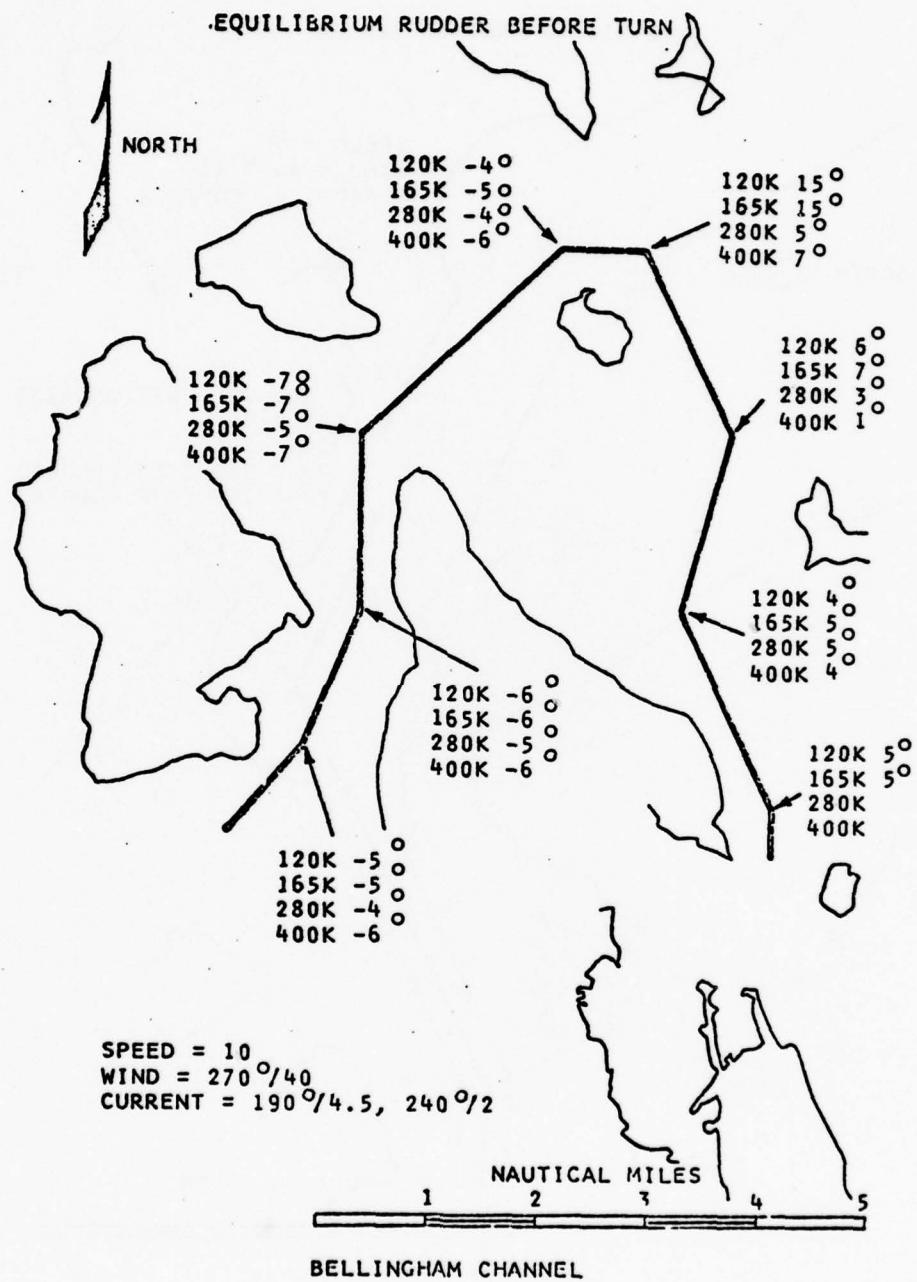




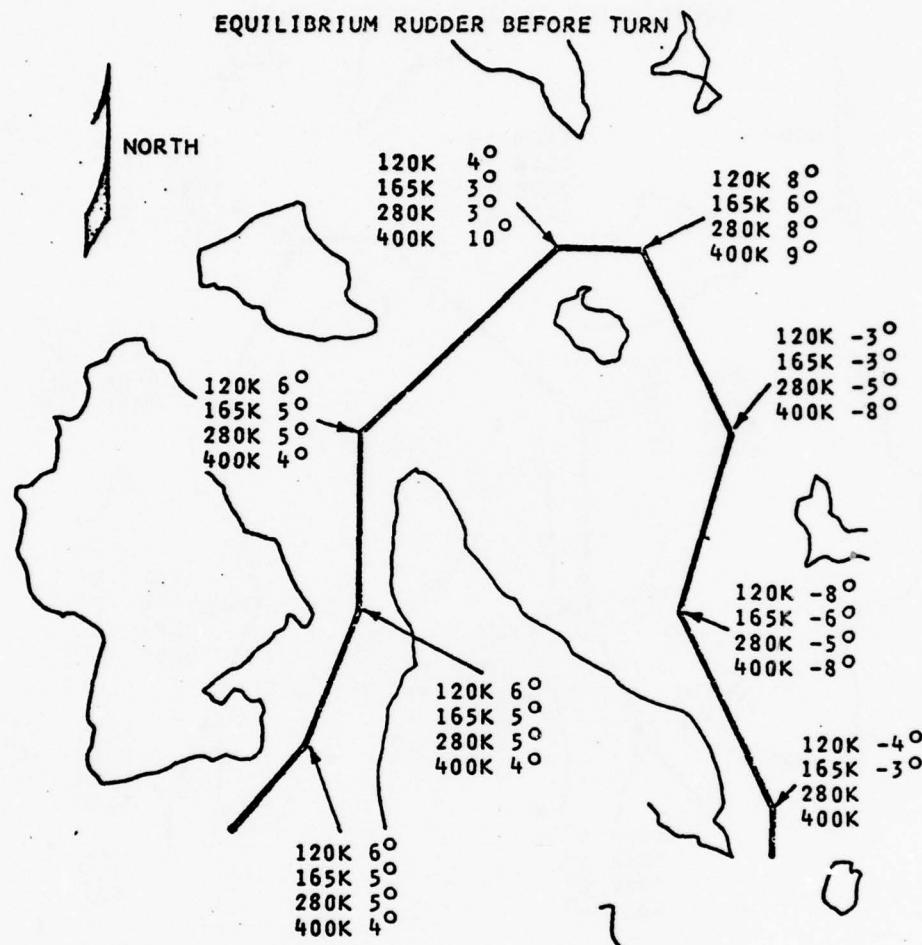








EQUILIBRIUM RUDDER BEFORE TURN

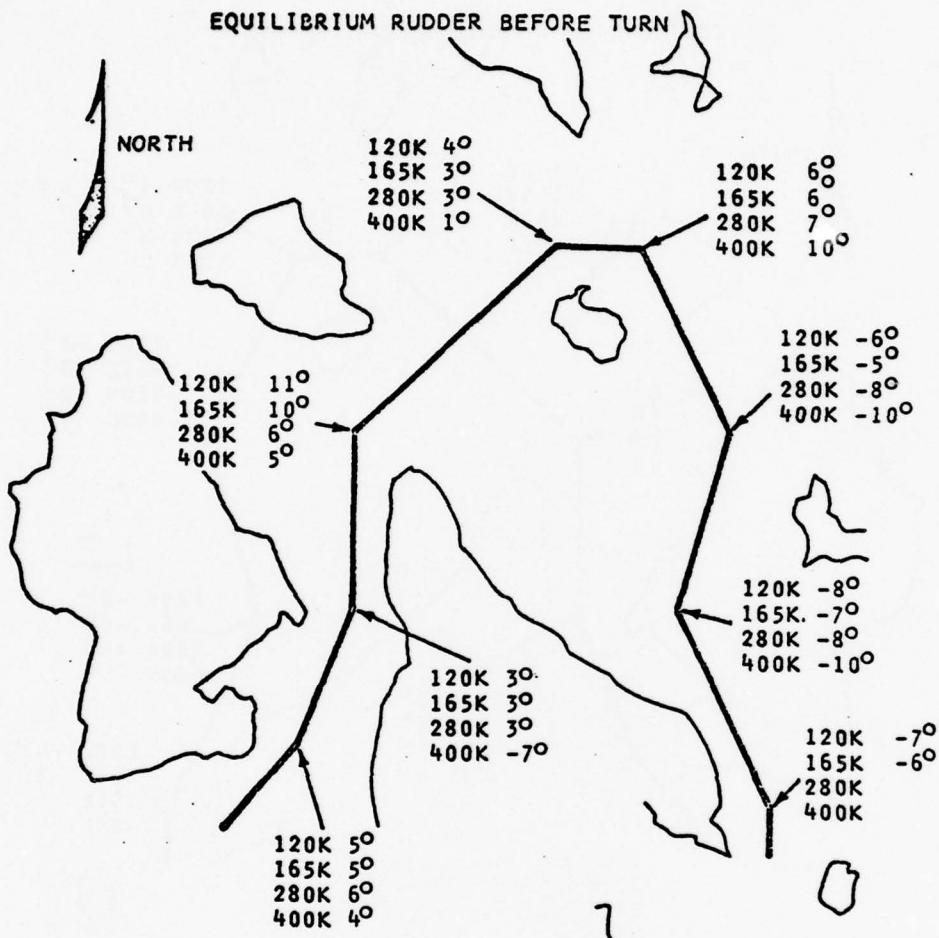


SPEED = 10
WIND = 090°/40
CURRENT = 190°/4.5, 240°/2

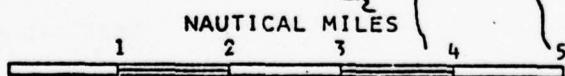
NAUTICAL MILES
1 2 3 4 5

BELLINGHAM CHANNEL

EQUILIBRIUM RUDDER BEFORE TURN

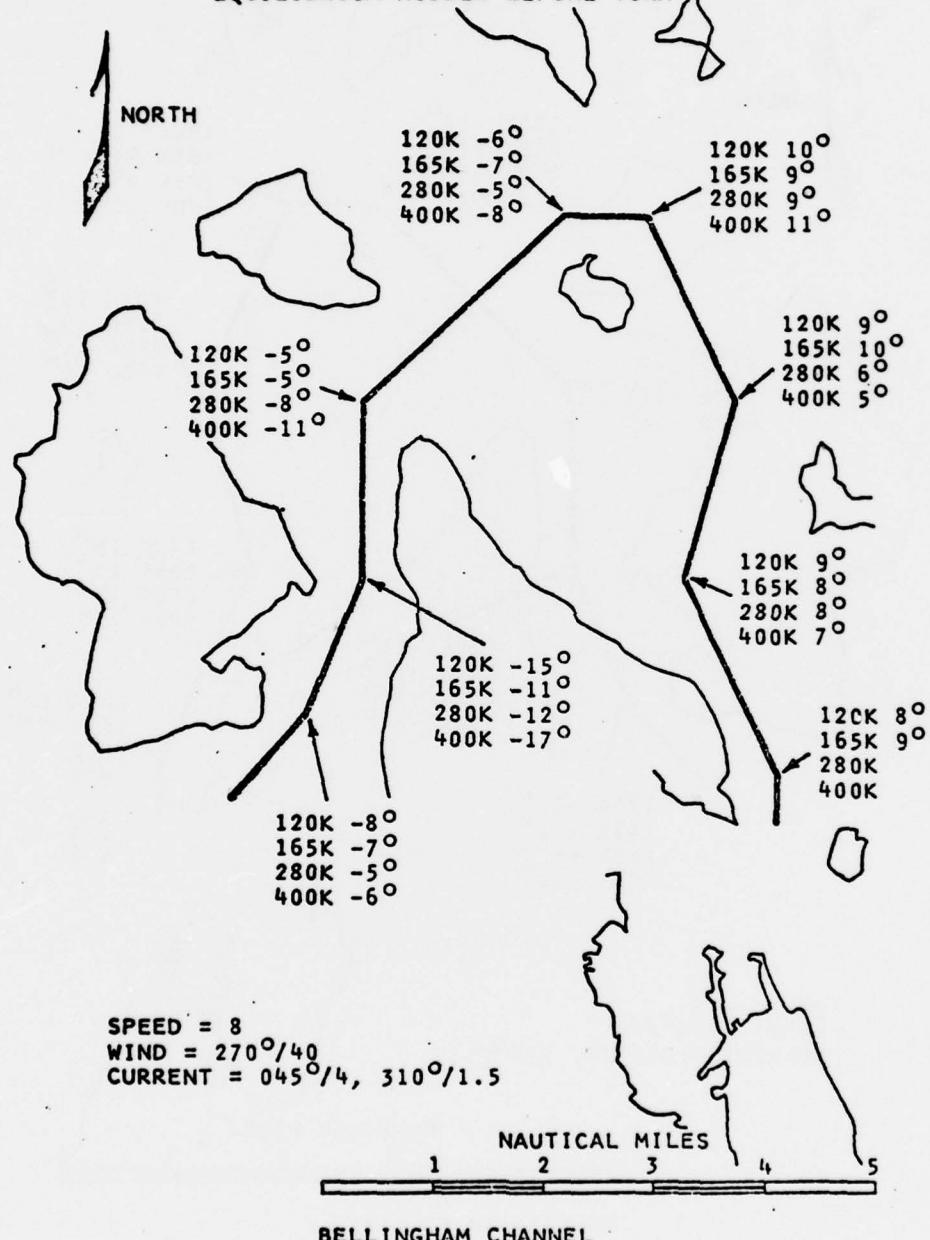


SPEED = 8
WIND = 090°/40
CURRENT = 045°/4, 310°/1.5

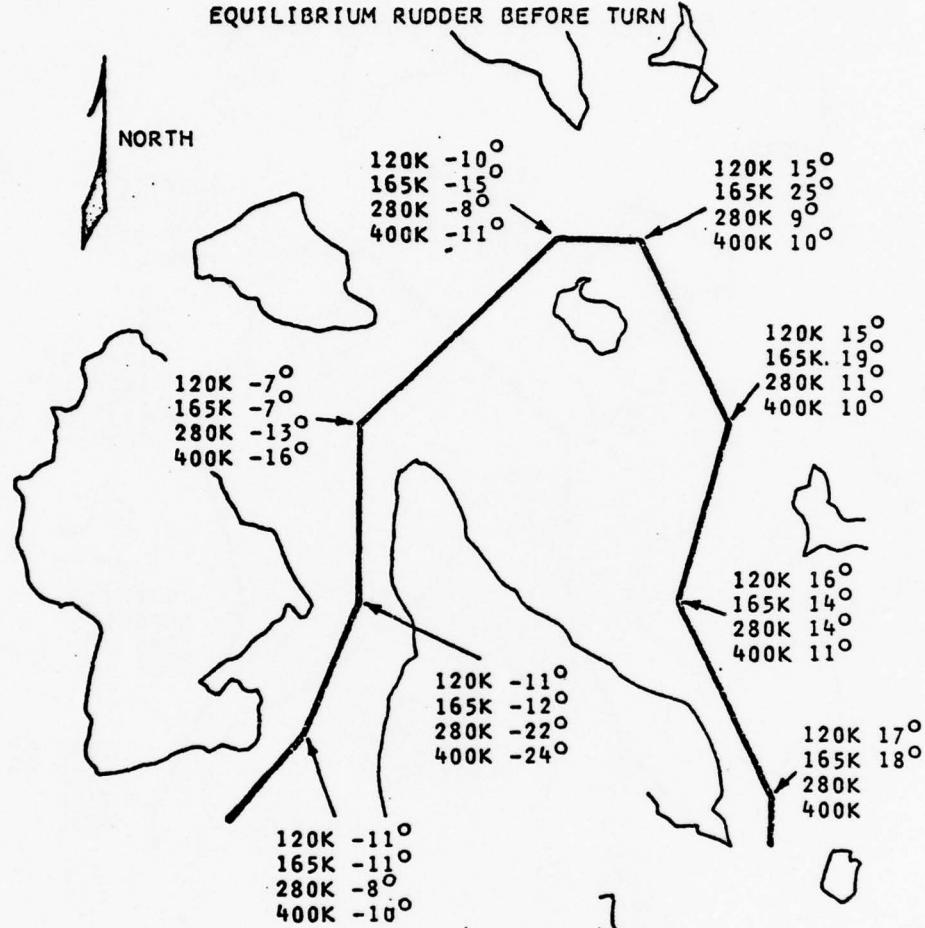


BELLINGHAM CHANNEL

EQUILIBRIUM RUDDER BEFORE TURN



EQUILIBRIUM RUDDER BEFORE TURN

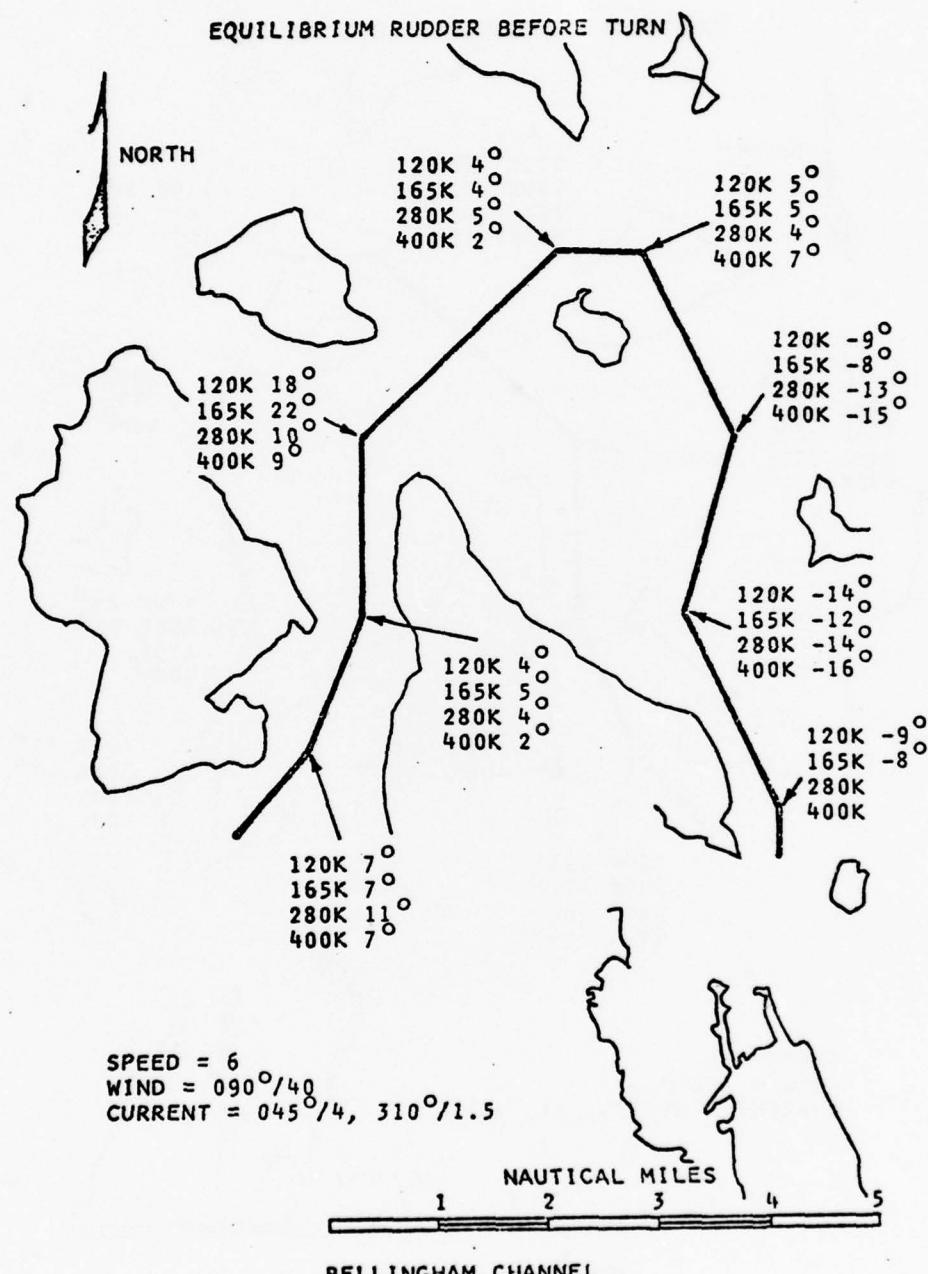


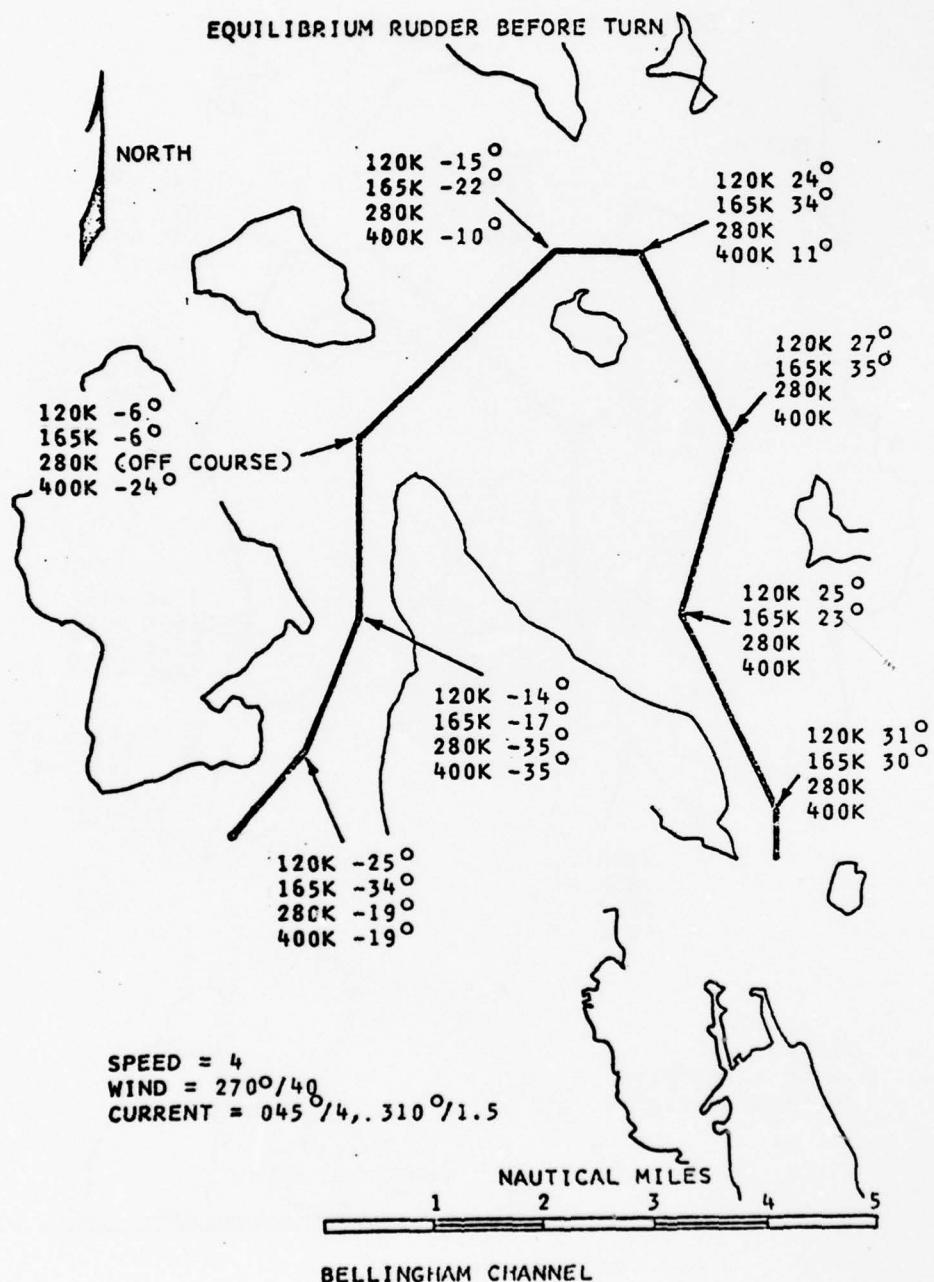
SPEED = 6
WIND = $270^\circ/40$
CURRENT = $045^\circ/4$, $310^\circ/1.5$

NAUTICAL MILES
1 2 3 4 5

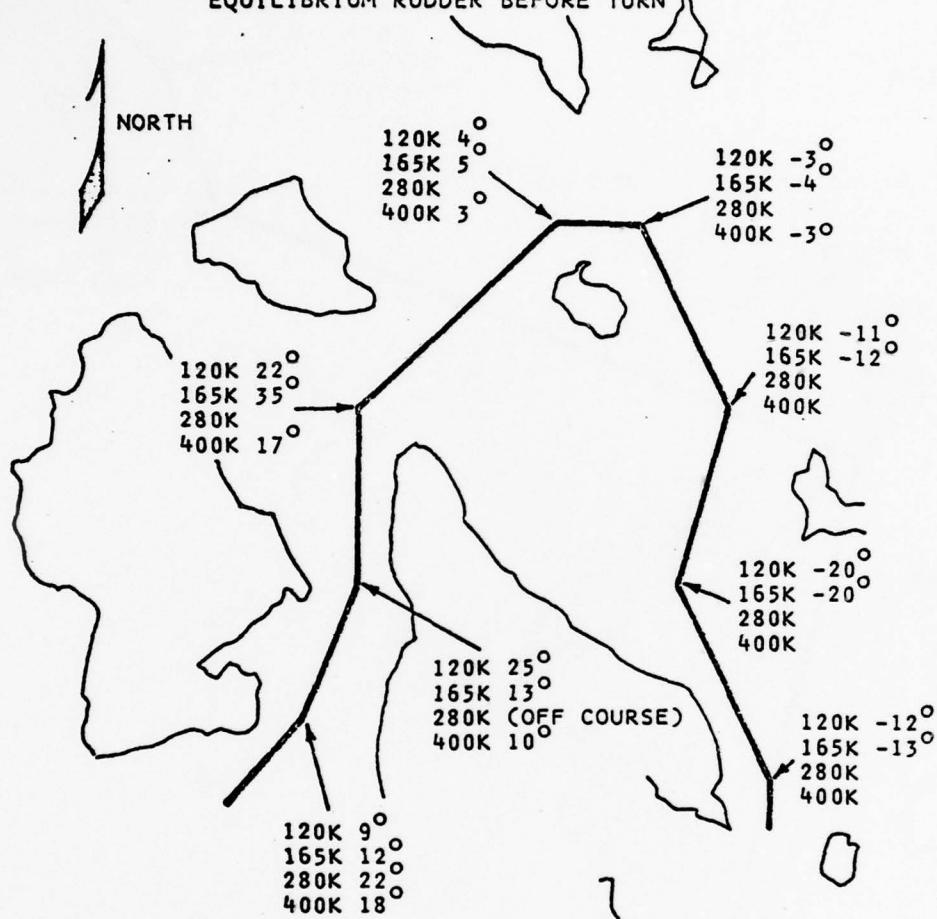
BELLINGHAM CHANNEL

EQUILIBRIUM RUDDER BEFORE TURN





EQUILIBRIUM RUDDER BEFORE TURN

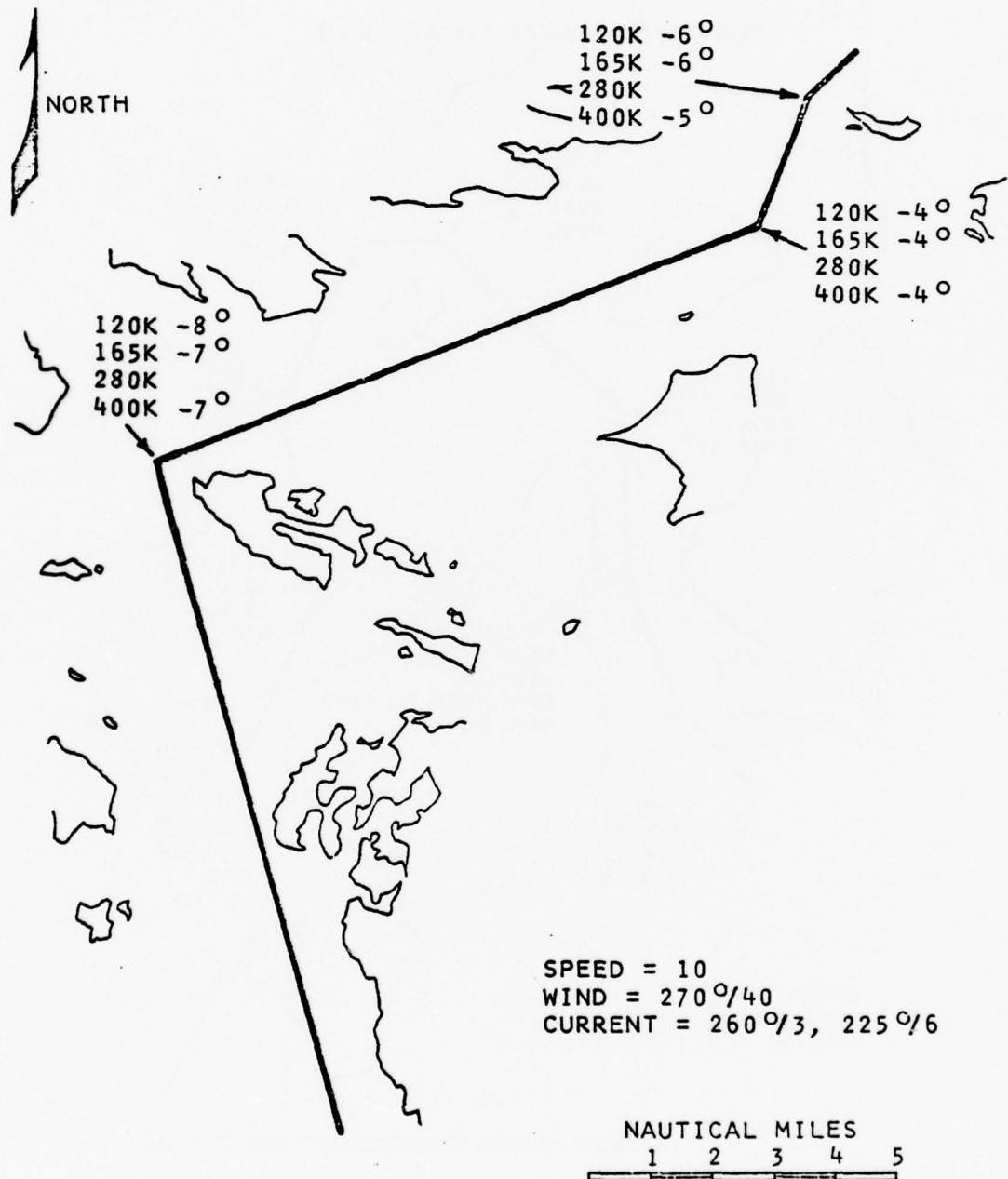


SPEED = 4
WIND = 090° / 40
CURRENT = 045° / 4, 310° / 1.5

NAUTICAL MILES
1 2 3 4 5

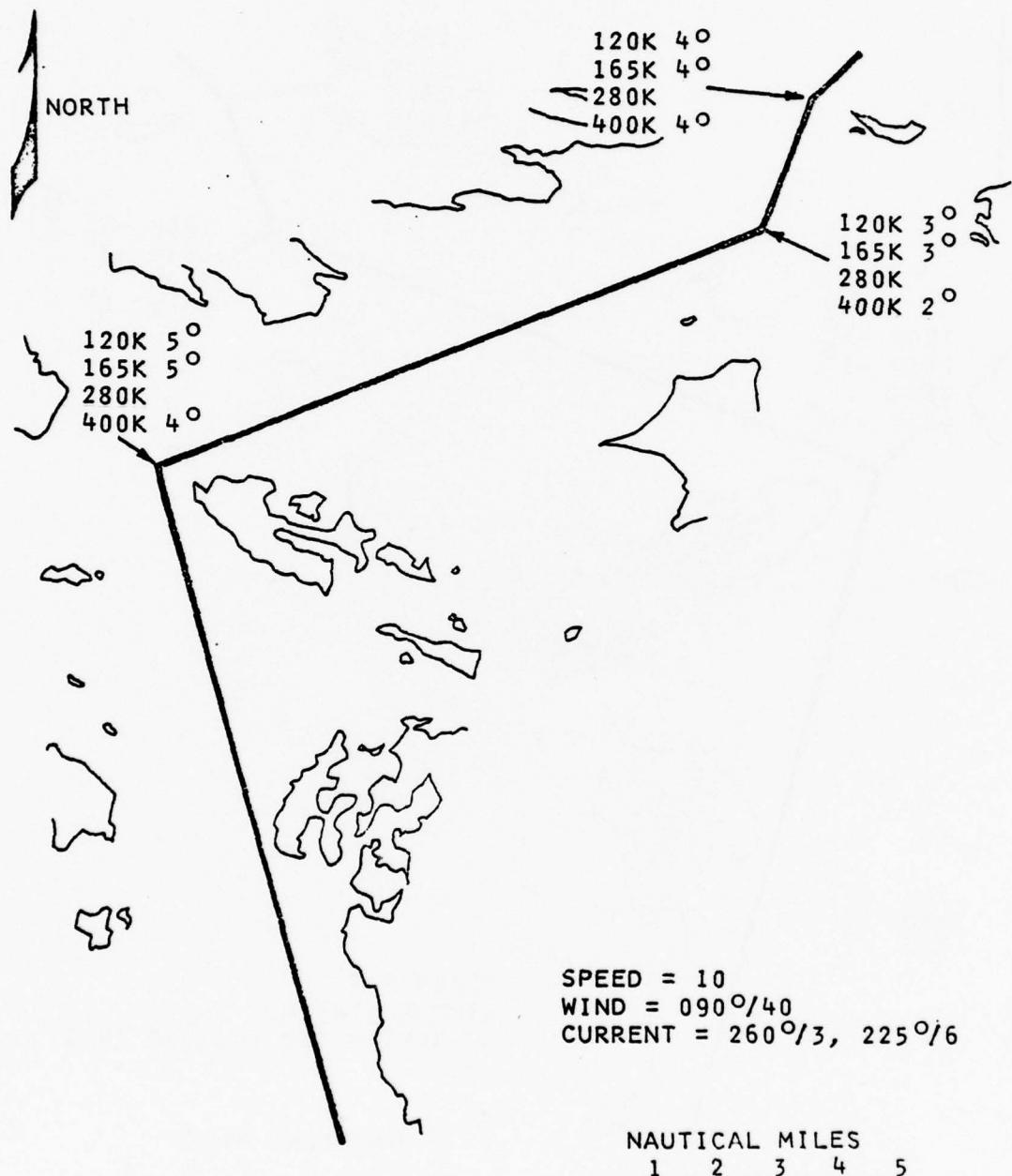
BELLINGHAM CHANNEL

EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

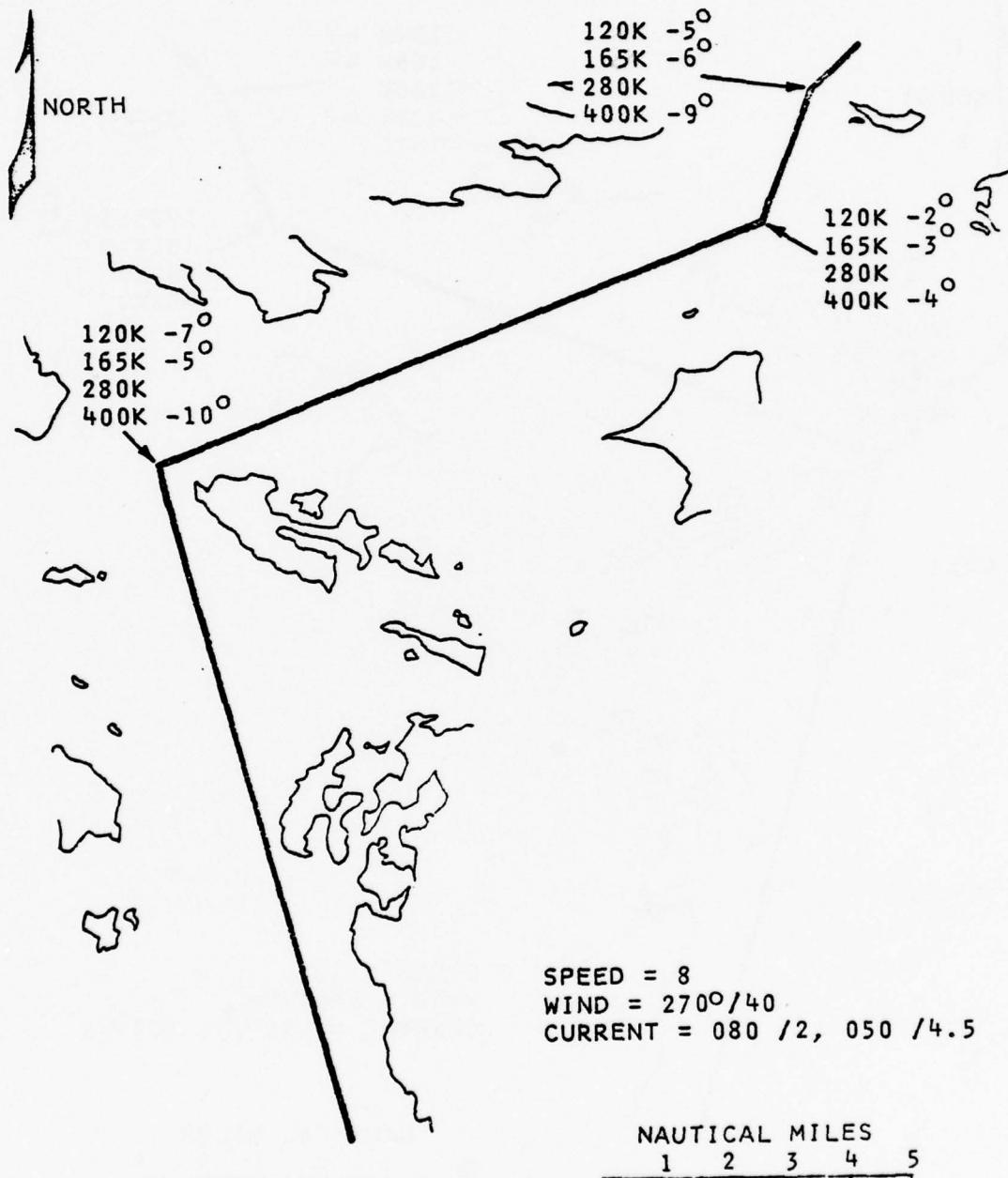
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

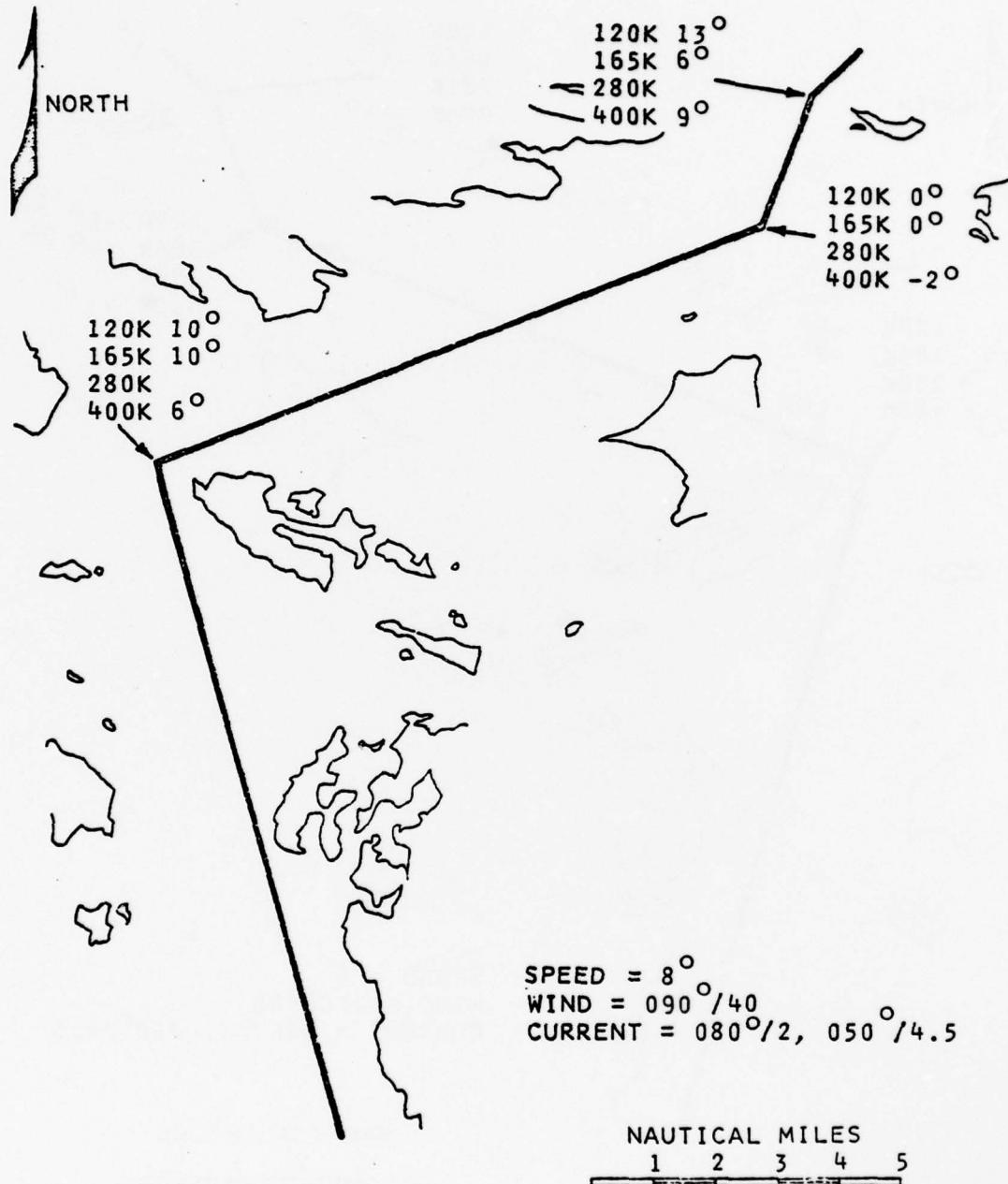
H-23

EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

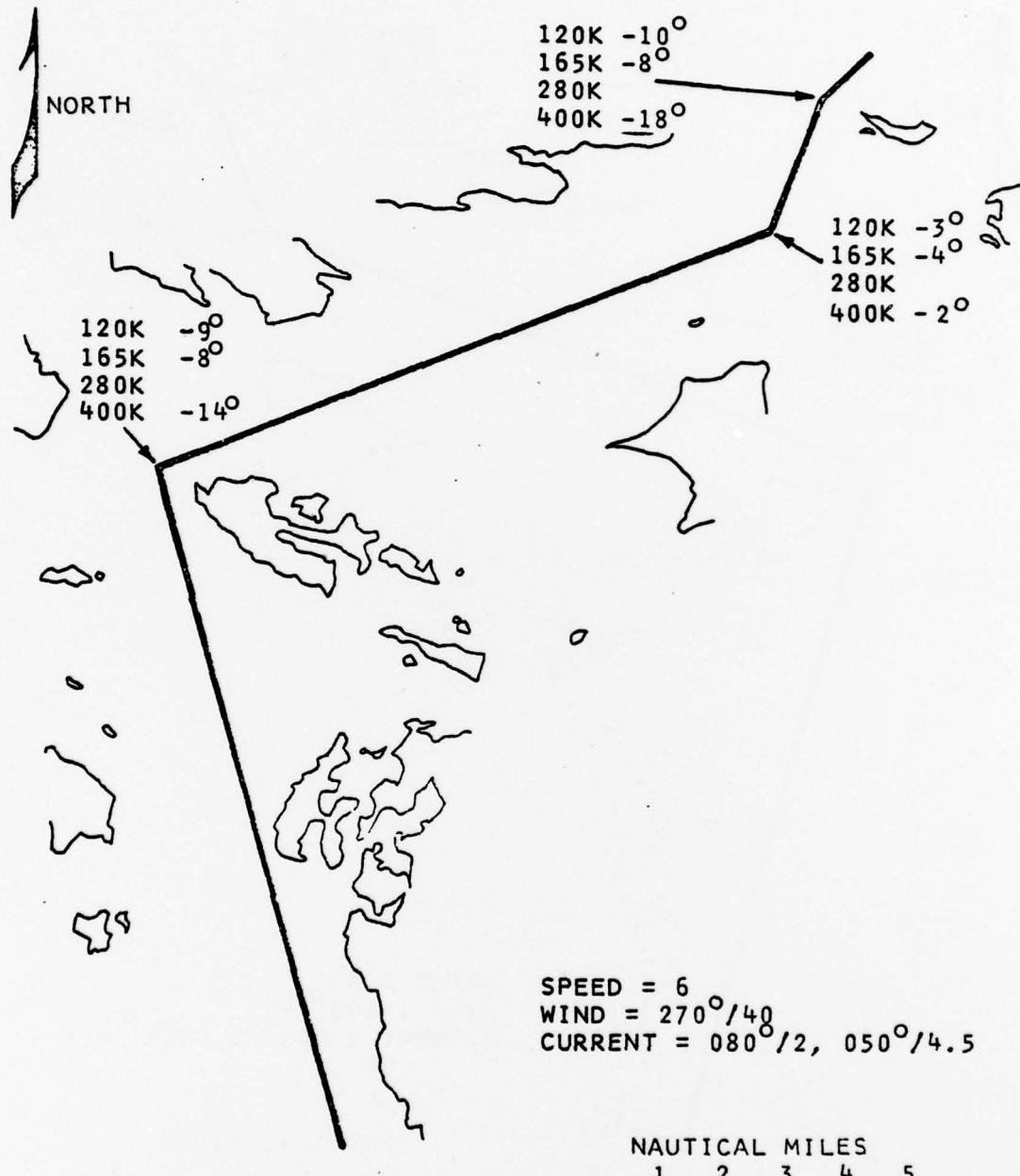
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

H-25

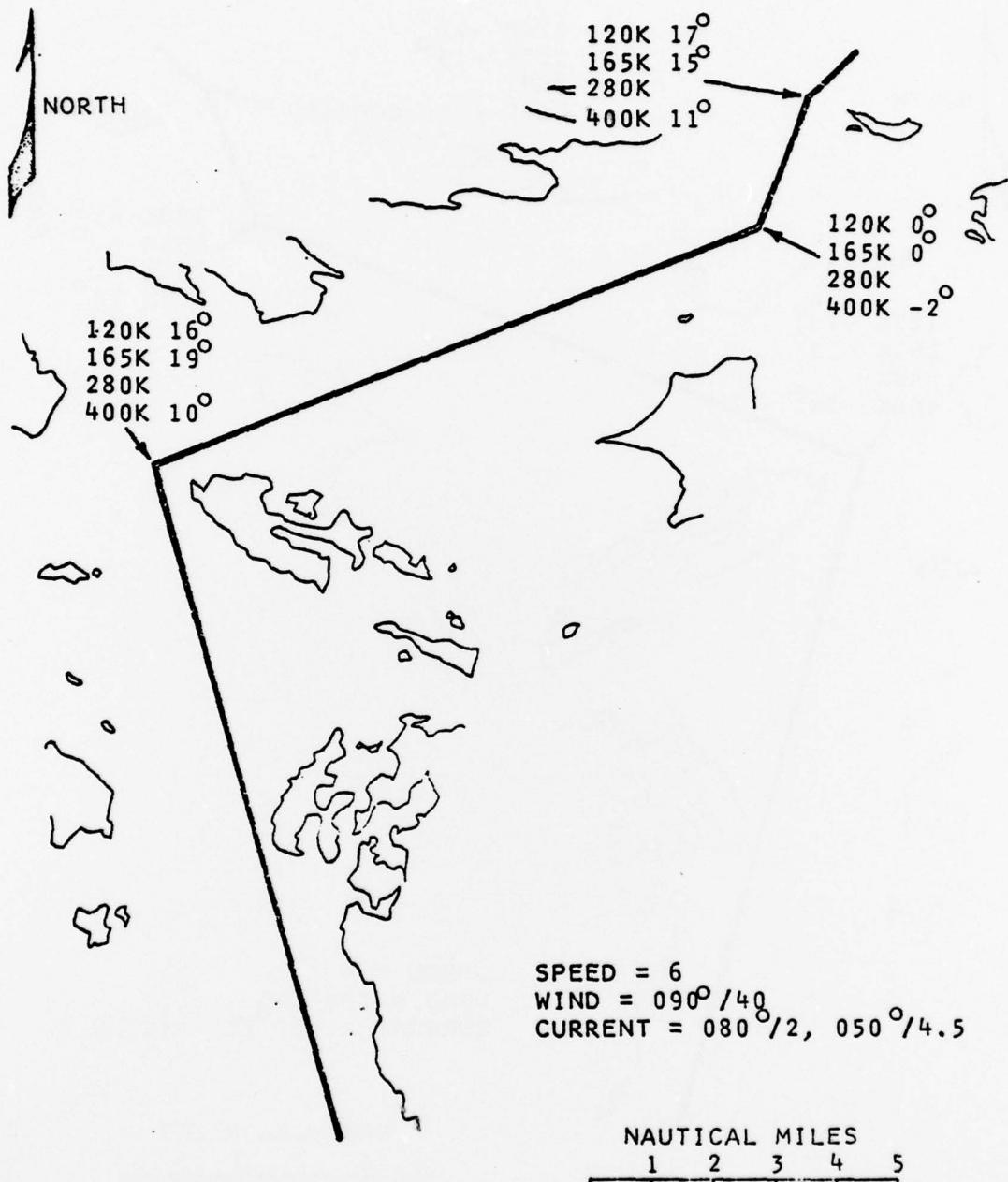
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

H-26

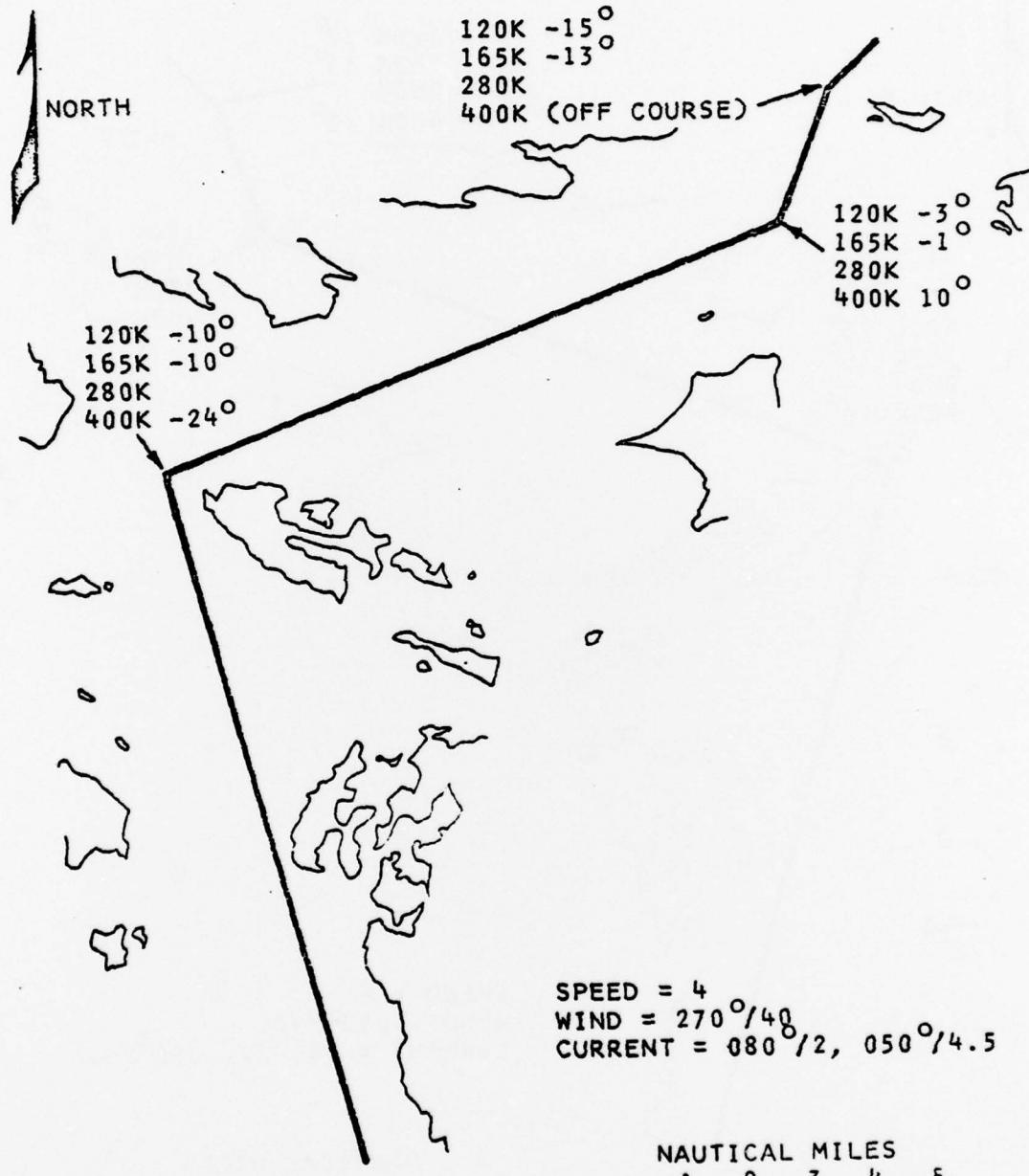
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

H-27

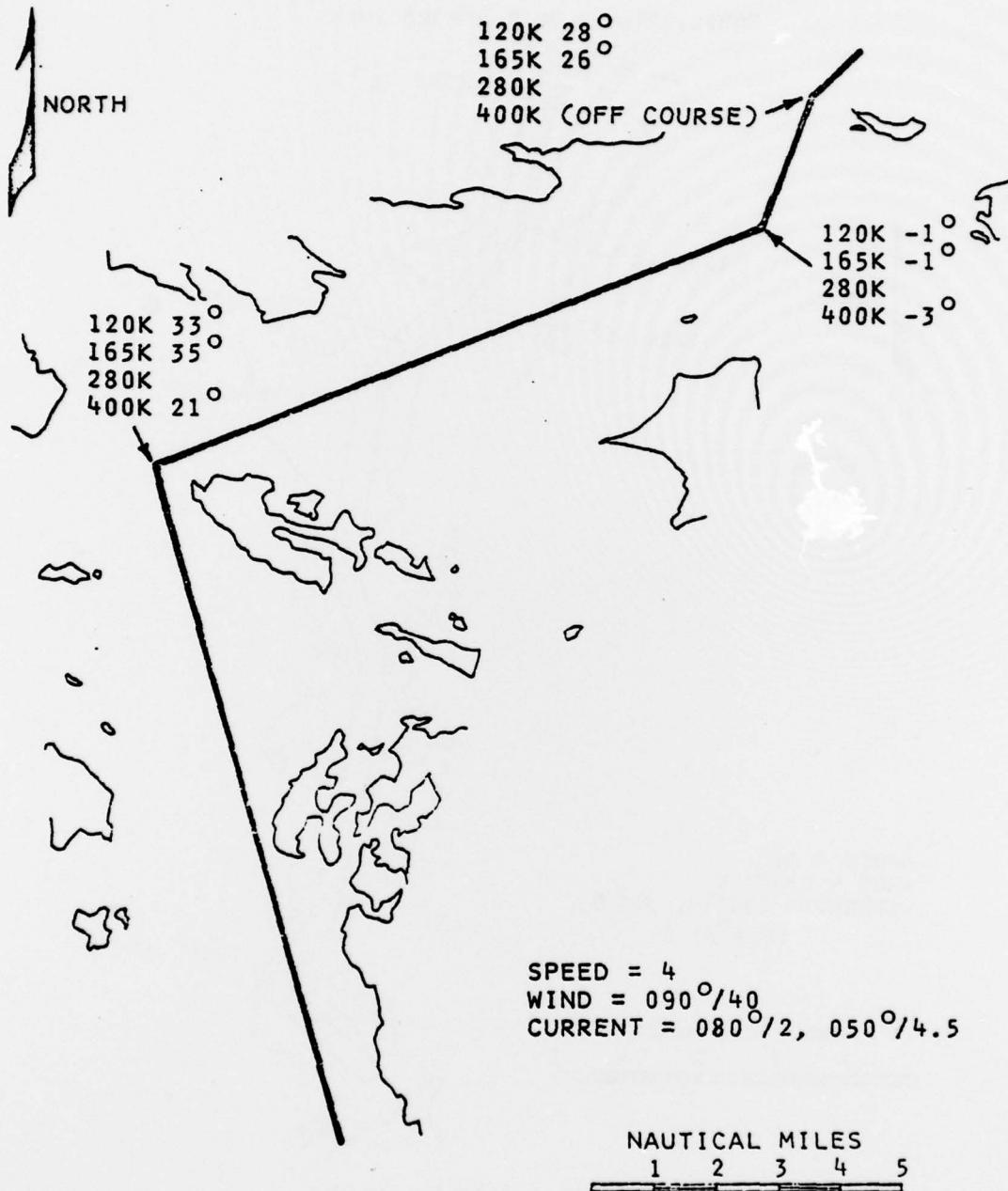
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

H-28

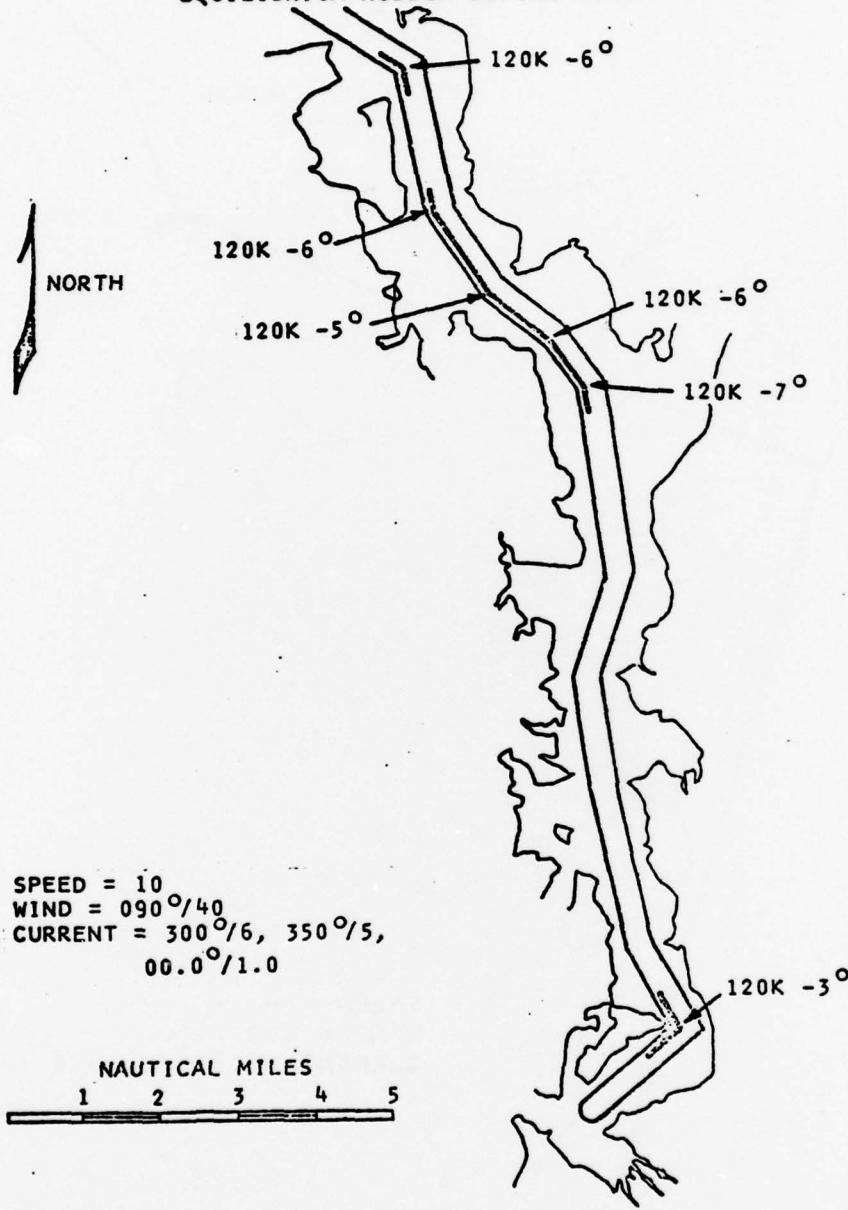
EQUILIBRIUM RUDDER BEFORE TURN



HARO STRAIT

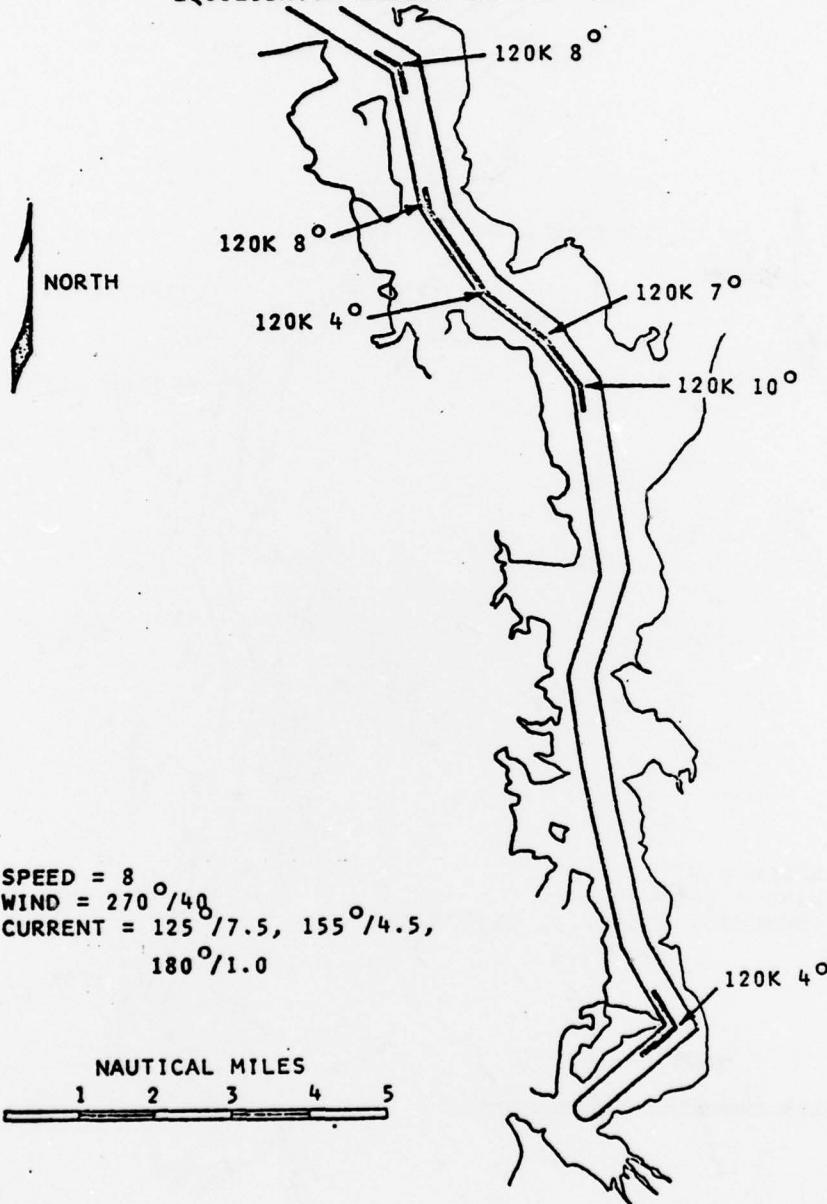
H-29

EQUILIBRIUM RUDDER BEFORE TURN



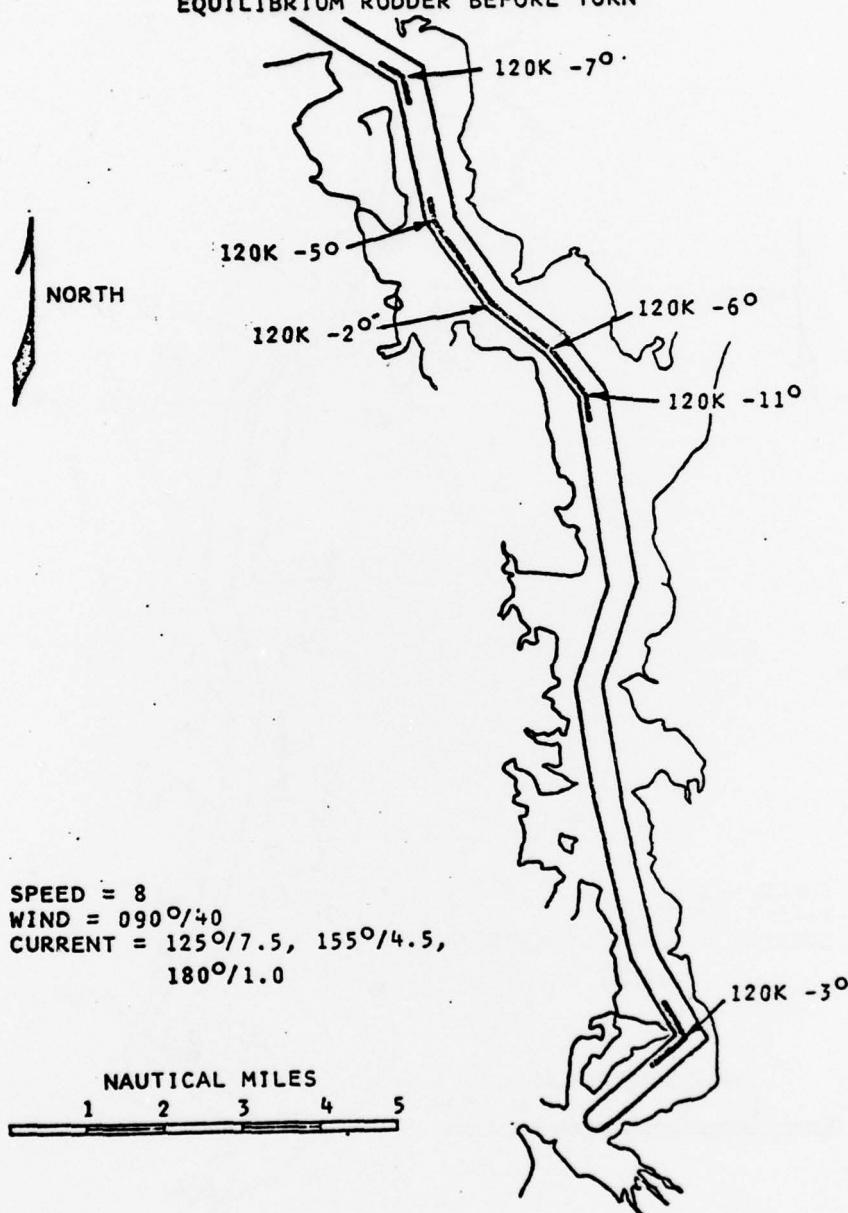
TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN



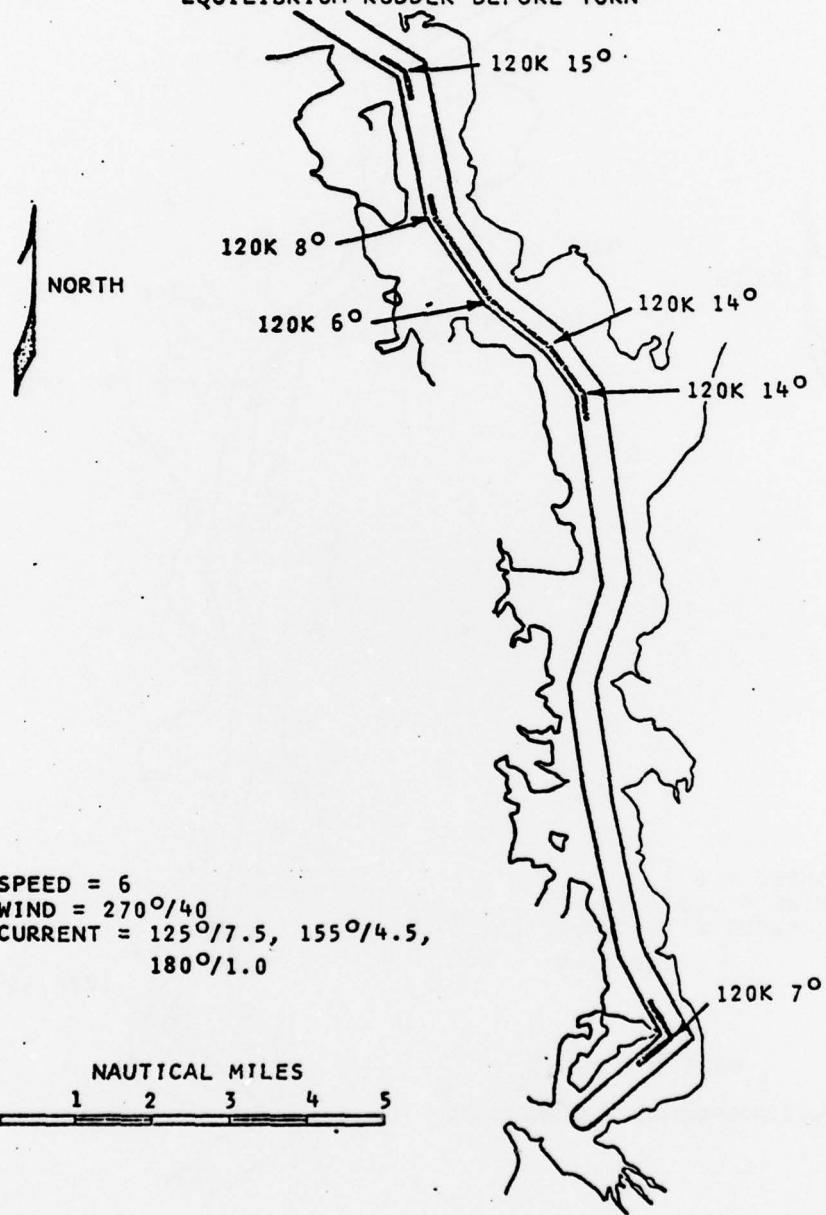
TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN



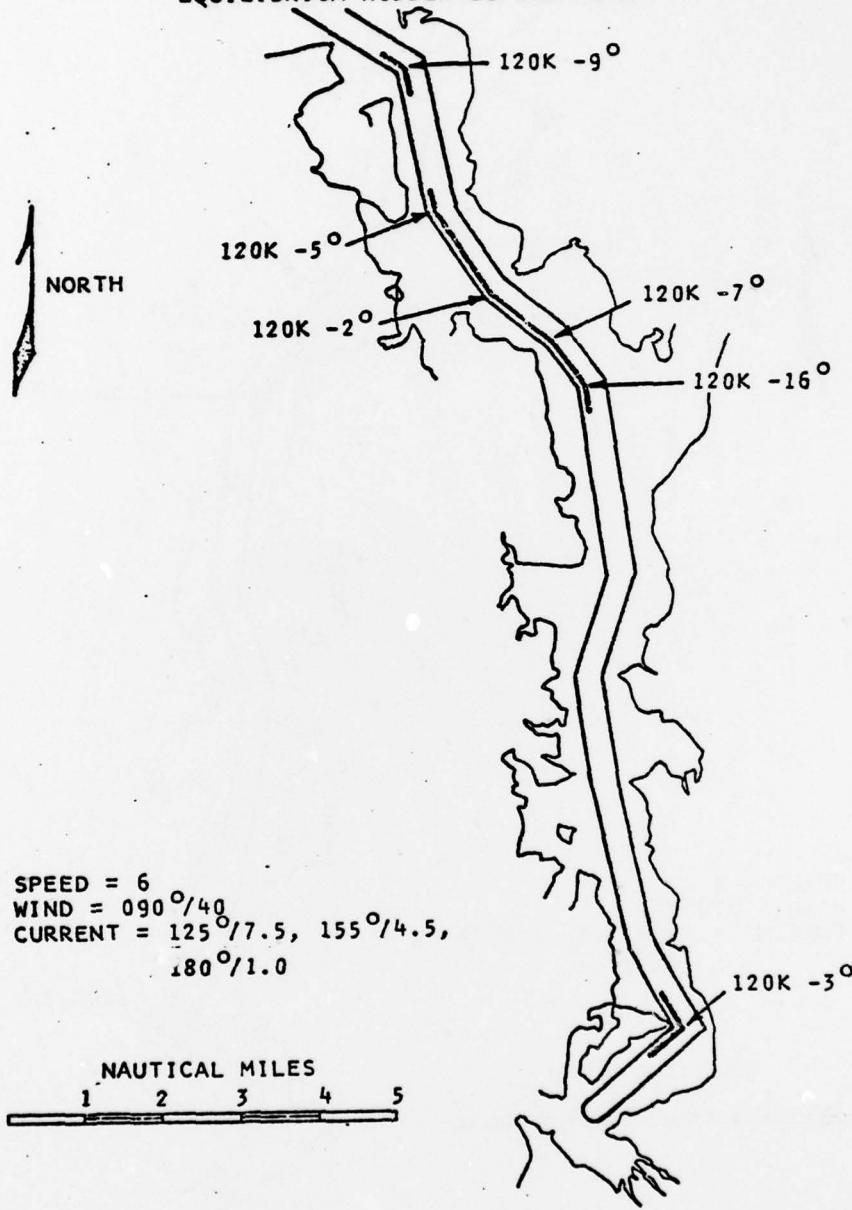
TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN



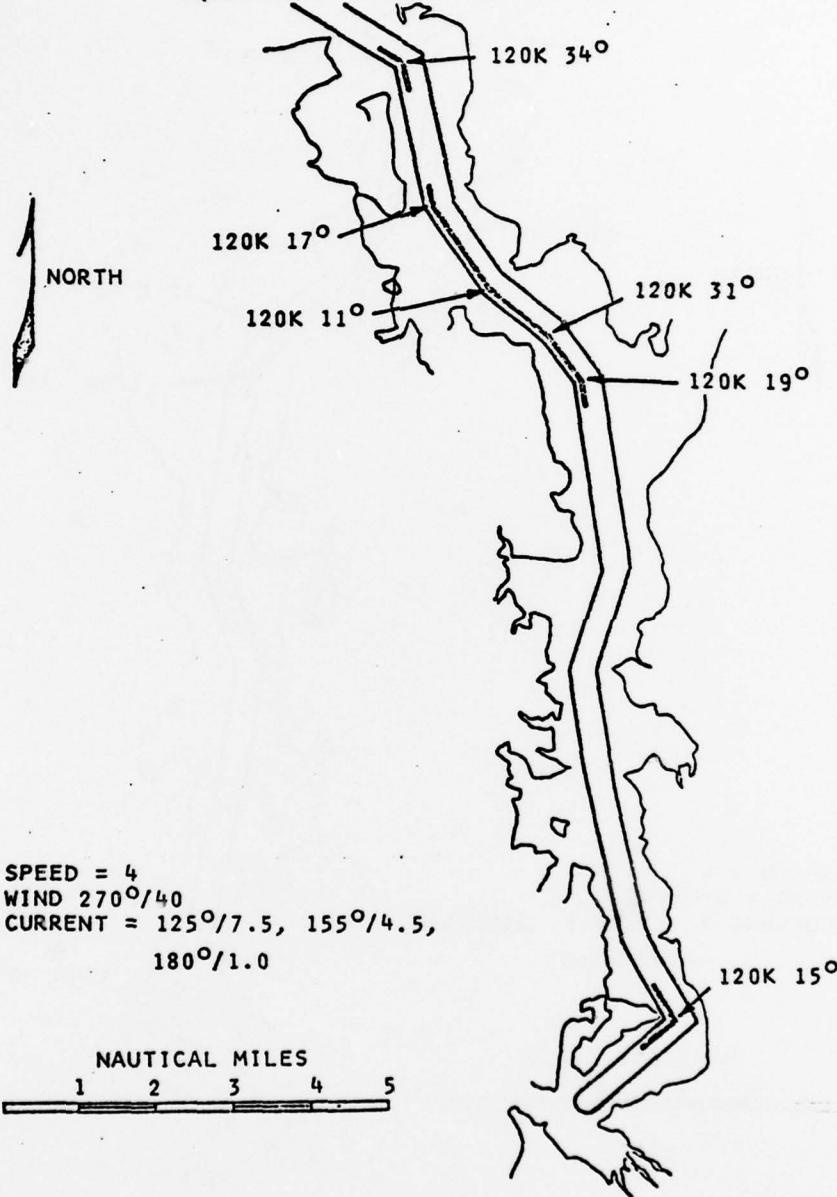
TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN

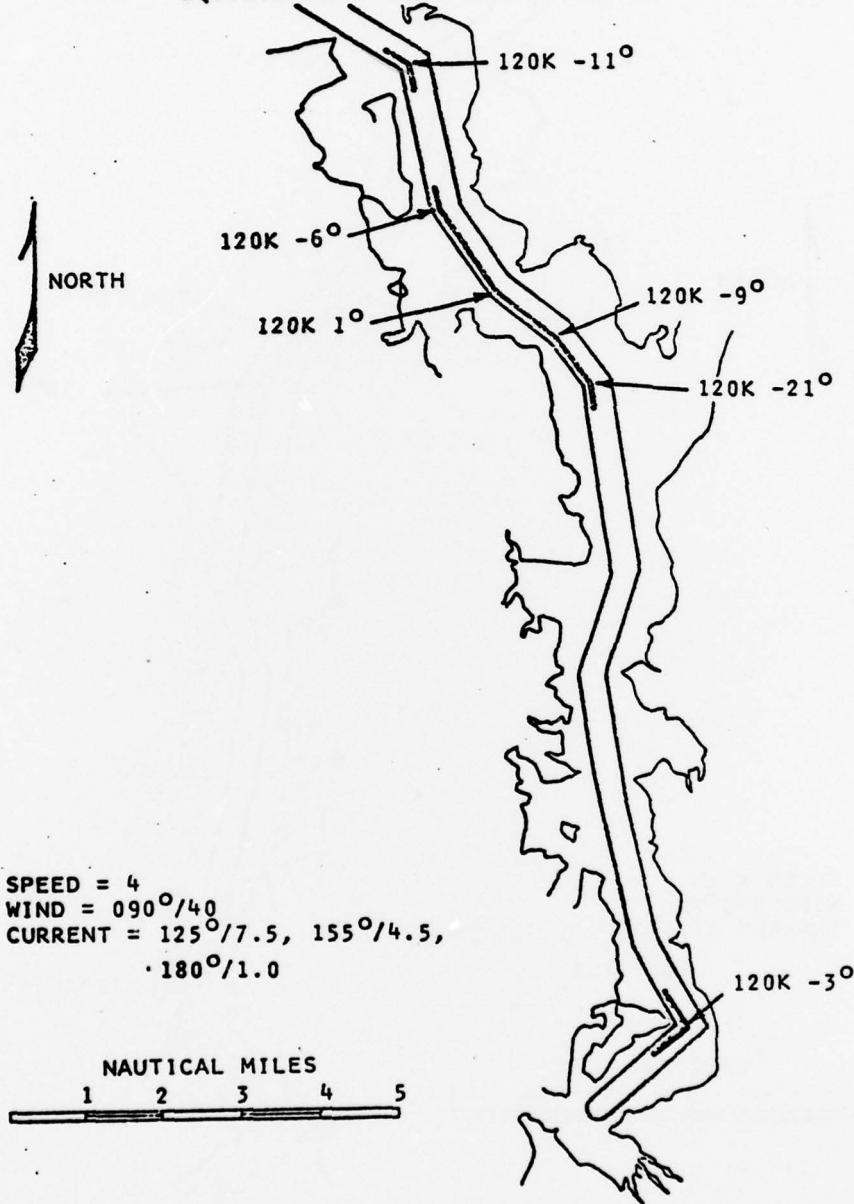


TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN

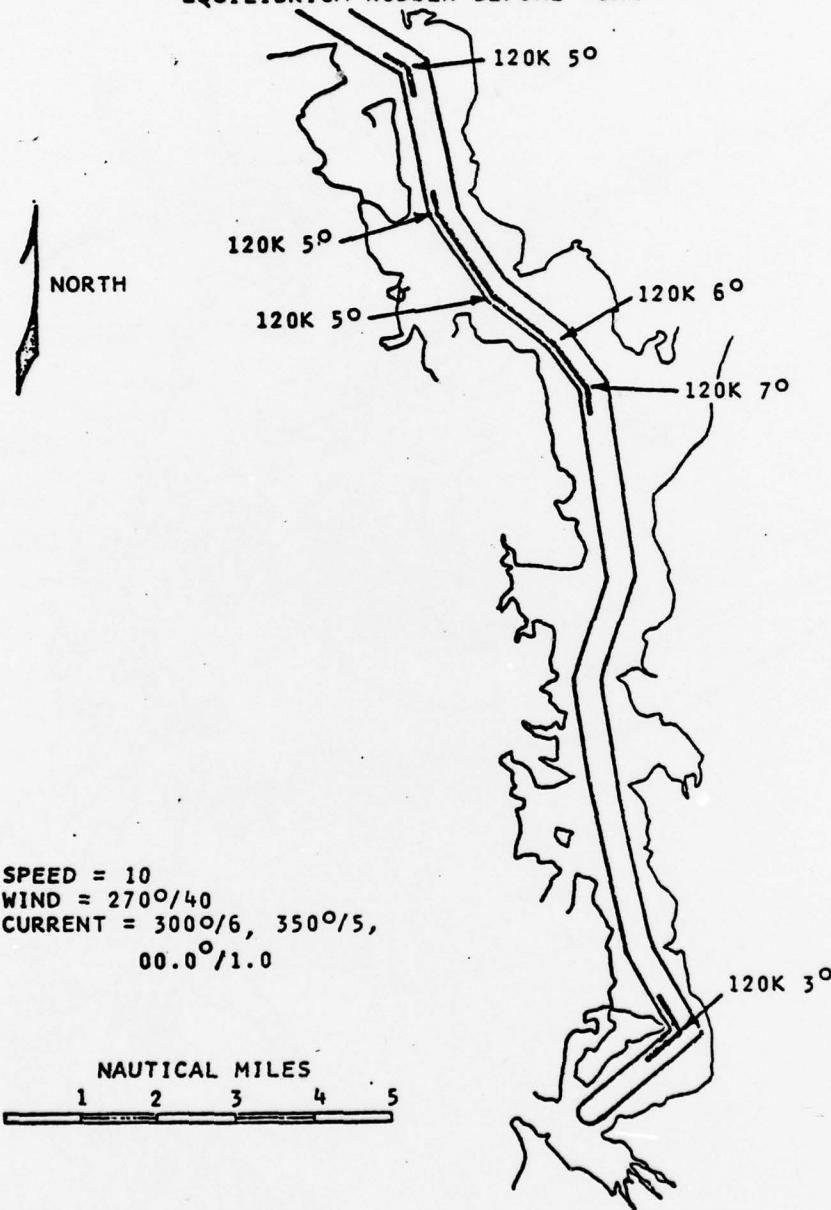


EQUILIBRIUM RUDDER BEFORE TURN



TACOMA VIA ADMIRALTY INLET

EQUILIBRIUM RUDDER BEFORE TURN



TACOMA VIA ADMIRALTY INLET

